

JAPAN

EDICT OF GOVERNMENT

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JIS B 9705-1 (2011) (English): Safety of
machinery -- Safety-related parts of control
systems -- Part 1: General principles for design

ISO INSIDE

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*The citizens of a nation must
honor the laws of the land.*

Fukuzawa Yukichi

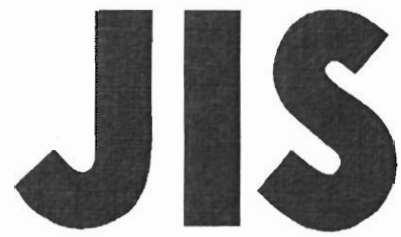
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**Safety of machinery—Safety-related
parts of control systems—Part 1:
General principles for design**

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Foreword

This translation has been made based on the original Japanese Industrial Standard revised by the Minister of Health, Labour and Welfare and the Minister of Economy, Trade and Industry through deliberations at the Japanese Industrial Standards Committee as the result of proposal for revision of Japanese Industrial Standard submitted by The Japan Machinery Federation (JMF) with the draft being attached, based on the provision of Article 12 Clause 1 of the Industrial Standardization Law applicable to the case of revision by the provision of Article 14.

Consequently **JIS B 9705-1:2000** is replaced with this Standard.

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Safety of machinery—Safety-related parts of control systems— Part 1: General principles for design

Introduction

This Japanese Industrial Standard has been prepared based on the second edition of **ISO 13849-1** published in 2006 without modifying the technical contents.

The portions with dotted underlines are the matters not given in the corresponding International Standard.

The structure of safety standards in the field of machinery is as follows as stated in **JIS B 9700-1**.

Type-A standards (basis standards) give basic concepts, principles for design and general aspects that can be applied to machinery.

Type-B standards (generic safety standards) deal with one or more safety aspect(s), or one or more type(s) of safeguards that can be used across a wide range of machinery:

- Type-B1 standards on particular safety aspects (e.g. safety distances, surface temperature, noise);
- Type-B2 standards on safeguards (e.g. two-hand controls, interlocking devices, pressure sensitive devices, guards).

Type-C standards (machinery safety standards) deal with detailed safety requirements for a particular machine or group of machines.

JIS B 9705-1 is a Type-B-1 standard as stated in **JIS B 9700-1**.

When provisions of a Type-C standard are different from those which are stated in Type-A or Type-B standards, the provisions of the Type-C standard take precedence over the provisions of the other standards for machines that have been designed and built according to the provisions of the Type-C standard.

JIS B 9705-1 is intended to give guidance to those involved in the design and assessment of control systems, and to those developing Type-B2 or Type-C standards.

As part of the overall risk reduction strategy at a machine, a designer will often choose to achieve some measure of risk reduction through the application of safeguards employing one or more safety functions.

Parts of machinery control systems that are assigned to provide safety functions and called safety-related parts of control systems (SRP/CS) and these can consist of hardware and software and can either be separate from the machine control system or an integral part of it. In addition to providing safety functions, SRP/CS can also provide operational functions (e.g. two-handed controls as a means of process initiation).

The ability of safety-related parts of control systems to perform a safety function under foreseeable conditions is allocated one of five levels, called performance levels (PL). These performance levels are defined in terms of probability of dangerous failure per hour (see table 3).

The probability of dangerous failure of the safety function depends on several factors, including hardware and software structure, the extent of fault detection mechanisms [diagnostic coverage (DC)], reliability of components [mean time of dangerous failure (MTTF_d)], common cause failure (CCF)], design process, operating stress, environmental conditions and operation procedures.

In order to assist the designer and help facilitate the assessment of achieved PL, this Standard employs a methodology based on the categorization of structures according to specific design criteria and specified behaviours under fault conditions. These categories are allocated one of five levels, termed Categories B, 1, 2, 3 and 4.

The performance levels and categories can be applied to safety-related parts of control systems, such as

- protective devices (e.g. two-hand control devices, interlocking devices), electro-sensitive protective devices (e.g. photoelectric barriers), pressure sensitive devices,
- control units (e.g. a logic unit for control functions, data processing, monitoring, etc.), and
- power control elements (e.g. relays, valves, etc.),

as well as to control systems carrying out safety functions at all kinds of machinery — from simple (e.g. small kitchen machines, or automatic doors and gates) to manufacturing installations (e.g. packaging machines, printing machines, presses).

This Standard is intended to provide a clear basis upon which the design and performance of any application of the SRP/CS (and the machine) can be assessed, for example, by a third party, in-house or by an independent test house.

JIS B 9961 and this Standard specify requirements for the design and implementation of safety-related control systems of machinery. The use of either of these Standards, in accordance with their scopes, can be presumed to fulfil the relevant essential safety requirements. The following table summarizes the scopes of **JIS B 9961** and this Standard.

Table 1 Recommended application of JIS B 9961 and JIS B 9705-1

Technology implementing the safety-related control function(s)		JIS B 9705-1	JIS B 9961
A	Non-electrical, e.g. hydraulics	X	Not covered
B	Electromechanical, e.g. relays, and/or non complex electronics	Restricted to designated architectures ^{a)} and up to PL=e	All architectures and up to SIL3
C	Complex electronics, e.g. programmable	Restricted to designated architectures ^{a)} and up to PL=d	All architectures and up to SIL3
D	A combined with B	Restricted to designated architectures ^{a)} and up to PL=e	X ^{c)}
E	C combined with B	Restricted to designated architectures ^{a)} and up to PL=d	All architectures and up to SIL3
F	C combined with A, or C combined with A and B	X ^{b)}	X ^{c)}
X indicates that this item is dealt with by the Standard shown in the column heading.			
Notes ^{a)} Designated architectures are defined in 6.2 in order to give a simplified approach for quantification of performance level.			
^{b)} For complex electronics: use designated architectures according to this Standard up to PL=d or any architecture according to JIS B 9961 .			
^{c)} For non-electrical technology, use parts in accordance with this Standard as subsystems.			

1 Scope

This Standard provides safety requirements and guidance on the principles for the design and integration of safety-related parts of control systems (SRP/CS), including the design of software. For these parts of SRP/CS, it specifies characteristics that include the performance level required for carrying out safety functions. It applies to SRP/CS, regardless of the type of technology and energy used (electrical, hydraulic, pneumatic, mechanical, etc.), for all kinds of machinery.

It does not specify the safety functions or performance levels that are to be used in a particular case.

This Standard provides specific requirements for SRP/CS using programmable electronic system(s).

It does not give specific requirements for the design of products which are parts of SRP/CS. Nevertheless, the principles given, such as categories or performance levels, can be used.

NOTE 1 Examples of products which are parts of SRP/CS: relays, solenoid valves, position switches, PLCs (programmable logic controllers), motor control units, two-hand control devices, pressure sensitive equipment. For the design of such products, it is important to refer to the specifically applicable Standards, e.g. **JIS B 9712**, **JIS B 9717-1** and **ISO 13856-2**.

NOTE 2 For the definition of required performance level, see **3.1.24**.

NOTE 3 The requirements provided in this Standard for programmable electronic systems are compatible with the methodology for the design and development of safety-related electrical, electronic and programmable electronic control systems for machinery given in **JIS B 9961**.

NOTE 4 For safety-related embedded software for components with $PL_r = e$ see **IEC 61508-3**, clause 7.

NOTE 5 See also table 1.

NOTE 6 The International Standard corresponding to this Standard and the symbol of degree of correspondence are as follows.

ISO 13849-1:2006 *Safety of machinery—Safety-related parts of control systems—Part 1: General principles for design* (IDT)

In addition, symbols which denote the degree of correspondence in the contents between the relevant International Standard and **JIS** are IDT (identical), MOD (modified), and NEQ (not equivalent) according to **ISO/IEC Guide 21-1**.

2 Normative references

The following standards contain provisions which, through reference in this text, constitute provisions of this Standard. The most recent editions (including amendments) indicated below shall be applied.

JIS B 9700-1 *Safety of machinery—Basic concepts, general principles for design—Part 1: Basic terminology, methodology*

NOTE : Corresponding International Standard: ISO 12100-1 *Safety of machinery—Basic concepts, general principles for design—Part 1: Basic terminology, methodology* (IDT)

JIS B 9700-2 *Safety of machinery—Basic concepts, general principles for design—Part 2: Technical principles*

NOTE : Corresponding International Standard: ISO 12100-2 *Safety of machinery—Basic concepts, general principles for design—Part 2: Technical principles* (IDT)

JIS B 9702 *Safety of machinery—Principles of risk assessment*

NOTE : Corresponding International Standard: ISO 14121 *Safety of machinery—Principles of risk assessment* (IDT)

ISO 13849-2 *Safety of machinery—Safety-related parts of control systems—Part 2: Validation*

IEC 60050-191 *International Electrotechnical Vocabulary. Chapter 191: Dependability and quality of service*, Amd.1:1999 and Amd.2:2002

IEC 61508-3 *Functional safety of electrical/electronic/programmable electronic safety-related systems—Part 3: Software requirements* and Corr.1:1999

IEC 61508-4 *Functional safety of electrical/electronic/programmable electronic safety-related systems—Part 4: Definitions and abbreviations* and Corr.1:1999

3 Terms, definitions, symbols and abbreviated terms

3.1 Terms and definitions

For the purposes of this document, the terms and definitions given in **JIS B 9700-1** and **IEC 60050-191** and the following apply.

3.1.1 safety-related part of a control system, SRP/CS

part of a control system that responds to safety-related input signals and generates safety-related output signals

NOTE 1 The combined safety-related parts of a control system start at the point where the safety-related input signals are initiated (including, for example, the actuating cam and the roller of the position switch) and end at the output of the power control elements (including, for example, the main contacts of a contactor).

NOTE 2 If monitoring systems are used for diagnostics, they are also considered as SRP/CS.

3.1.2 category

classification of the safety-related parts of a control system in respect of their resistance to faults and their subsequent behaviour in the fault condition, and which is achieved by the structural arrangement of the parts, fault detection and/or by their reliability

3.1.3 fault

state of an item characterized by the inability to perform a required function, excluding the inability during preventive maintenance or other planned actions, or due to lack of external resources

NOTE 1 A fault is often the result of a failure of the item itself, but may exist without prior failure.

(See **IEC 60050-191, 05-01.**)

NOTE 2 In this Standard, “fault” means random fault.

NOTE 3 “Fault” is translated into Japanese as “HUGUAI (SYÔGAI)” in **JIS B 9700-1** which has the same meaning as “SYÔGAI” defined in this Standard. “HUGUAI” is mainly used for machineries.

3.1.4 failure

termination of the ability of an item to perform a required function

NOTE 1 After a failure, the item has a fault.

NOTE 2 “Failure” is an event, as distinguished from “fault”, which is a state.

NOTE 3 The concept as defined does not apply to items consisting of software only.
(See **IEC 60050-191, 04-01.**)

NOTE 4 Failures which only affect the availability of the process under control are outside of the scope of this Standard.

3.1.5 dangerous failure

failure which has the potential to put the SRP/CS in a hazardous or fail-to-function state

NOTE : Whether or not the potential is realized can depend on the channel architecture of the system; in redundant systems a dangerous hardware failure is less likely to lead to the overall dangerous or fail-to-function state.

(Adapted from IEC 61508-4, definition 3.6.7.)

3.1.6 common cause failure, CCF

failures of different items, resulting from a single event, where these failures are not consequences of each other

(See IEC 60050-191 Amd.1, 04-23.)

NOTE : Common cause failures should not be confused with common mode failures.

3.1.7 systematic failure

failure related in a deterministic way to a certain cause, which can only be eliminated by a modification of the design or of the manufacturing process, operational procedures, documentation or other relevant factors

NOTE 1 Corrective maintenance without modification will usually not eliminate the failure cause.

NOTE 2 A systematic failure can be induced by simulating the failure cause.

(See IEC 60050-191, 04-19.)

NOTE 3 Examples of causes of systematic failures include human error in

- the safety requirements specification,
- the design, manufacture, installation, operation of the hardware, and
- the design, implementation, etc., of the software.

3.1.8 muting

temporary automatic suspension of a safety function(s) by the SRP/CS

3.1.9 manual reset

function within the SRP/CS used to restore manually one or more safety functions before re-starting a machine

3.1.10 harm

physical injury or damage to health

(See JIS B 9700-1, 3.5.)

3.1.11 hazard

potential source of harm

NOTE 1 A hazard can be qualified in order to define its origin (e.g. mechanical hazard, electrical hazard) or the nature of the potential harm (e.g. electric shock hazard, cutting hazard, toxic hazard, fire hazard).

NOTE 2 The hazard envisaged in this definition:

- either is permanently present during the intended use of the machine (e.g. motion of hazardous moving elements, electric arc during a welding phase, unhealthy posture, noise emission, high temperature);
- or may appear unexpectedly (e.g. explosion, crushing hazard as a consequence of an unintended/unexpected start-up, ejection as a consequence of a breakage, fall as a consequence of acceleration/deceleration).

(See **JIS B 9700-1, 3.6.**)

3.1.12 hazardous situation

circumstance in which a person is exposed to at least one hazard, the exposure having immediately or over a long period of time the potential to result in harm

(See **JIS B 9700-1, 3.9.**)

3.1.13 risk

combination of the probability of occurrence of harm and the severity of that harm

(See **JIS B 9700-1, 3.11.**)

3.1.14 residual risk

risk remaining after protective measures have been taken

See figure 2.

(Adapted from **JIS B 9700-1**, definition **3.12.**)

3.1.15 risk assessment

overall process comprising risk analysis and risk evaluation

(See **JIS B 9700-1, 3.13.**)

3.1.16 risk analysis

combination of the specification of the limits of the machine, hazard identification and risk estimation

(See **JIS B 9700-1, 3.14.**)

3.1.17 risk evaluation

judgement, on the basis of risk analysis, of whether risk reduction objectives have been achieved

(See **JIS B 9700-1, 3.16.**)

3.1.18 intended use of a machine

use of the machine in accordance with the information provided in the instructions for use

(See **JIS B 9700-1, 3.22.**)

3.1.19 reasonably foreseeable misuse

use of a machine in a way not intended by the designer, but which may result from readily predictable human behaviour

(See **JIS B 9700-1, 3.23.**)

3.1.20 safety function

function of the machine whose failure can result in an immediate increase of the risk(s)

(See **JIS B 9700-1, 3.28.**)

3.1.21 monitoring

safety function which ensures that a protective measure is initiated if the ability of a component or an element to perform its function is diminished or if the process conditions are changed in such a way that a decrease of the amount of risk reduction is generated

3.1.22 programmable electronic system, PES

system for control, protection or monitoring dependent for its operation on one or more programmable electronic devices, including all elements of the system such as power supplies, sensors and other input devices, contactors and other output devices

(Adapted from **IEC 61508-4**, definition **3.3.2.**)

3.1.23 performance level, PL

discrete level used to specify the ability of safety-related parts of control systems to perform a safety function under foreseeable conditions

NOTE : See **4.5.1.**

3.1.24 required performance level, PL_r

performance level (PL) applied in order to achieve the required risk reduction for each safety function

See figures 2 and **A.1.**

3.1.25 mean time to dangerous failure, MTTF_d

expectation of the mean time to dangerous failure

(Adapted from **JIS B 9961**, definition **3.2.34.**)

3.1.26 diagnostic coverage, DC

measure of the effectiveness of diagnostics, which may be determined as the ratio between the failure rate of detected dangerous failures and the failure rate of total dangerous failures

NOTE : Diagnostic coverage can exist for the whole or parts of a safety-related system. For example, diagnostic coverage could exist for sensors and/or logic system and/or final elements.

(Adapted from **IEC 61508-4**, definition **3.8.6.**)

3.1.27 protective measure

measure intended to achieve risk reduction

Example 1 Implemented by the designer: inherent design, safeguarding and complementary protective measures, information for use.

Example 2 Implemented by the user: organization (safe working procedures, supervision, permit-to-work systems), provision and use of additional safeguards, personal protective equipment, training.

(Adapted from **JIS B 9700-1**, definition **3.18**.)

3.1.28 mission time, T_M

period of time covering the intended use of an SRP/CS

3.1.29 test rate, r_t

frequency of automatic tests to detect faults in an SRP/CS, reciprocal value of diagnostic test interval

3.1.30 demand rate, r_d

frequency of demands for a safety-related action of the SRP/CS

3.1.31 repair rate, r_r

reciprocal value of the period of time between detection of a dangerous failure by either an online test or obvious malfunction of the system and the restart of operation after repair or system/component replacement

NOTE : The repair time does not include the span of time needed for failure-detection.

3.1.32 machine control system

system which responds to input signals from parts of machine elements, operators, external control equipment or any combination of these and generates output signals causing the machine to behave in the intended manner

NOTE : The machine control system can use any technology or any combination of different technologies (e.g. electrical/electronic, hydraulic, pneumatic, mechanical).

3.1.33 safety integrity level, SIL

discrete level (one out of a possible four) for specifying the safety integrity requirements of the safety functions to be allocated to the E/E/PE (electric/electronic/programmable electronic) safety-related systems, where safety integrity level 4 (SIL4) has the highest level of safety integrity and safety integrity level 1 (SIL1) has the lowest

(See **IEC 61508-4**, **3.5.6**.)

3.1.34 limited variability language, LVL

type of language that provides the capability of combining predefined, application-specific library functions to implement the safety requirements specifications

(Adapted from **IEC 61511-1**, definition **3.2.81.1.2**.)

NOTE 1 Typical examples of LVL (ladder logic, function block diagram) are given in **JIS B 3503**.

NOTE 2 A typical example of a system using LVL: PLC.

3.1.35 full variability language, FVL

type of language that provides the capability of implementing a wide variety of functions and applications

Example : C, C++, Assembler.

(Adapted from **IEC 61511-1**, definition **3.2.81.1.3**.)

NOTE 1 A typical example of systems using FVL: embedded systems.

NOTE 2 In the field of machinery, FVL is found in embedded software and rarely in application software.

3.1.36 application software

software specific to the application, implemented by the machine manufacturer, and generally containing logic sequences, limits and expressions that control the appropriate inputs, outputs, calculations and decisions necessary to meet the SRP/CS requirements

3.1.37 embedded software, firmware, system software

software that is part of the system supplied by the control manufacturer and which is not accessible for modification by the user of the machinery

NOTE : Embedded software is usually written in FVL.

3.2 Symbols and abbreviated terms

See table 2.

Table 2 Symbols and abbreviated terms

Symbol or abbreviation	Description	Definition or occurrence
a, b, c, d, e	Denotation of performance levels	Table 3
AOPD	Active optoelectronic protective device (e.g. light barrier)	Annex H
B, 1, 2, 3, 4	Denotation of categories	Table 7
B_{10d}	Number of cycles until 10 % of the components fail dangerously (for pneumatic and electromechanical components)	Annex C
Cat.	Category	3.1.2
CC	Current converter	Annex I
CCF	Common cause failure	3.1.6
DC	Diagnostic coverage	3.1.26
DC_{avg}	Average diagnostic coverage	E.2
F, F1, F2	Frequency and/or time of exposure to the hazard	A.2.2
FB	Function block	4.6.3
FVL	Full variability language	3.1.35
FMEA	Failure modes and effects analysis	7.2

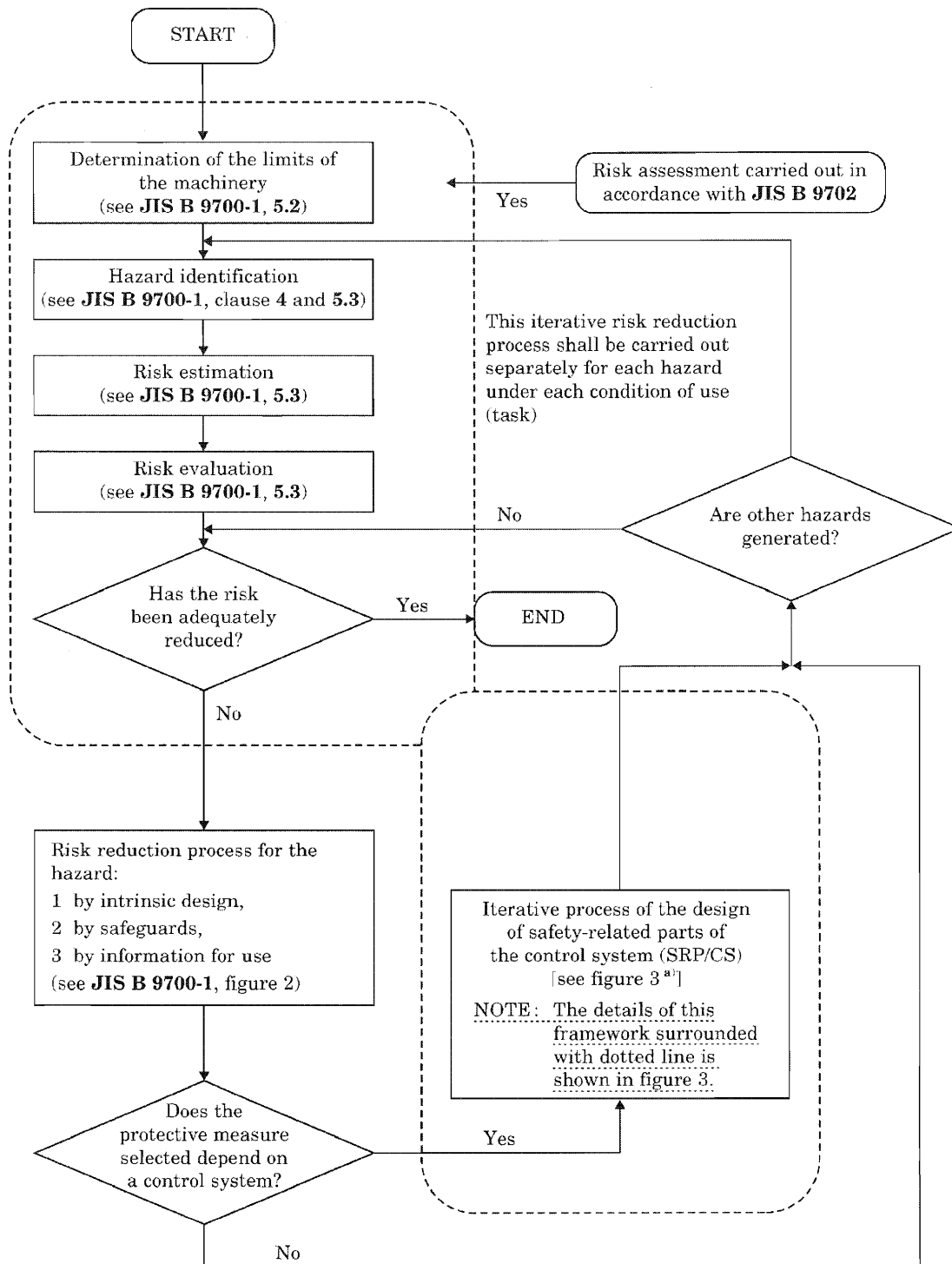
Table 2 (concluded)

Symbol or abbreviation	Description	Definition or occurrence
I, I1, I2	Input device, e.g. sensor	6.2
i, j	Index for counting	Annex D
I/O	Inputs/outputs	Table E.1
i_{ab}, i_{bc}	Interconnecting means	Figure 4
K1A, K1B	Contactors	Annex I
L, L1, L2	Logic	6.2
LVL	Limited variability language	3.1.34
M	Motor	Annex I
MTTF	Mean time to failure	Annex C
MTTF _d	Mean time to dangerous failure	3.1.25
n, N, \tilde{N}	Number of items	6.3, D.1
N_{low}	Number of SRP/CS with PL _{low} in a combination of SRP/CS	6.3
O, O1, O2, OTE	Output device, e.g. actuator	6.2
P, P1, P2	Possibility of avoiding the hazard	A.2.3
PES	Programmable electronic system	3.1.22
PL	Performance level	3.1.23
PLC	Programmable logic controller	Annex I
PL _{low}	Lowest performance level of an SRP/CS in a combination of SRP/CS	6.3
PL _r	Required performance level	3.1.24
r_d	Demand rate	3.1.30
RS	Rotation sensor	Annex I
S, S1, S2	Severity of injury	A.2.1
SW1A, SW1B, SW2	Position switches	Annex I
SIL	Safety integrity level	Table 4
SRASW	Safety-related application software	4.6.3
SRESW	Safety-related embedded software	4.6.2
SRP	Safety-related part	General
SRP/CS	Safety-related part of a control system	3.1.1
TE	Test equipment	6.2
T_M	Mission time	3.1.28

4 Design considerations

4.1 Safety objectives in design

The SRP/CS shall be designed and constructed so that the principles of **JIS B 9700-1** and **JIS B 9702** are fully taken into account (see figures 1 and 3). All intended use and reasonable foreseeable misuse shall be considered.



Note ^{a)} Refers to this Standard, figure 3.

Figure 1 Overview of risk assessment/risk reduction

4.2 Strategy for risk reduction

4.2.1 General

The strategy for risk reduction at the machine is given in **JIS B 9700-1**, clause 5, and further guidance is given in **JIS B 9700-2**, clauses 4 and 5. This strategy covers the whole life cycle of the machine.

The hazard analysis and risk reduction process for a machine requires that hazards are eliminated or reduced through a hierarchy of measures:

- hazard elimination or risk reduction by design (see **JIS B 9700-2**, clause 4);
- risk reduction by safeguarding and possibly complementary protective measures (see **JIS B 9700-2**, clause 5);
- risk reduction by the provision of information for use about the residual risk (see **JIS B 9700-2**, clause 6).

4.2.2 Contribution to the risk reduction by the control system

The purpose in following the overall design procedure for the machine is to achieve the safety objectives (see 4.1). The design of the SRP/CS to provide the required risk reduction is an integral subset of the overall design procedure for the machine. The SRP/CS provides safety function(s) at a PL which achieves the required risk reduction. In providing safety function(s), either as an inherently safe part of the design or as a control for a safeguard or protective device, the design of the SRP/CS is a part of the strategy for risk reduction. This is an iterative process and is illustrated in figures 1 and 3.

For each safety function, the characteristics (see clause 5) and the required performance level shall be specified and documented in the safety requirements specification.

In this Standard the performance levels are defined in terms of probability of dangerous failure per hour. Five performance levels (a to e) are set out, with defined ranges of probability of a dangerous failure per hour (see table 3).

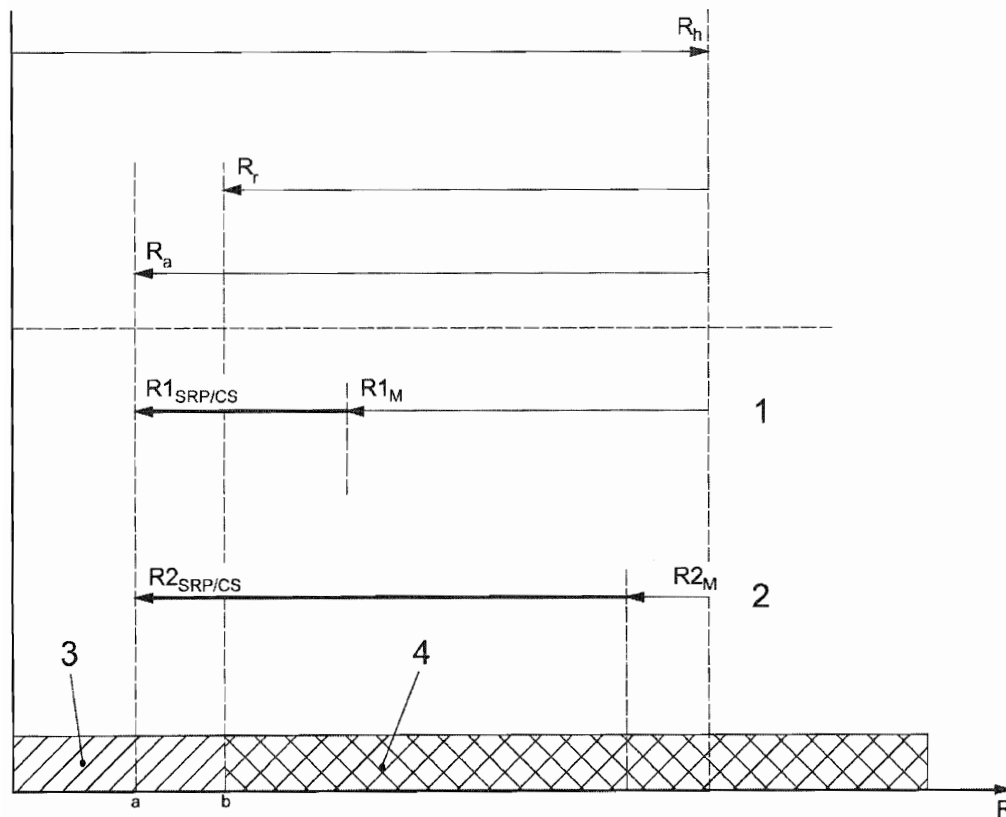
Table 3 Performance levels (PL)

PL	Average probability of dangerous failure per hour (<i>PFH</i> _d) [1/h]
a	$10^{-5} \leq PFH_d < 10^{-4}$
b	$3 \times 10^{-6} \leq PFH_d < 10^{-5}$
c	$10^{-6} \leq PFH_d < 3 \times 10^{-6}$
d	$10^{-7} \leq PFH_d < 10^{-6}$
e	$10^{-8} \leq PFH_d < 10^{-7}$
NOTE : Besides the average probability of dangerous failure per hour other measures are also necessary to achieve the PL.	

From the risk assessment (see **JIS B 9702**) at the machine, the designer shall decide the contribution to the reduction of risk which needs to be provided by each relevant safety function which is carried out by the SRP/CS(s). This contribution does not cover

the overall risk of the machinery under control, e.g. not the overall risk of a mechanical press, or washing machine is considered, but that part of risk reduced by the application of particular safety functions. Examples of such functions are the stopping function initiated by using an electro-sensitive protective device on a press or the door-locking function of a washing machine.

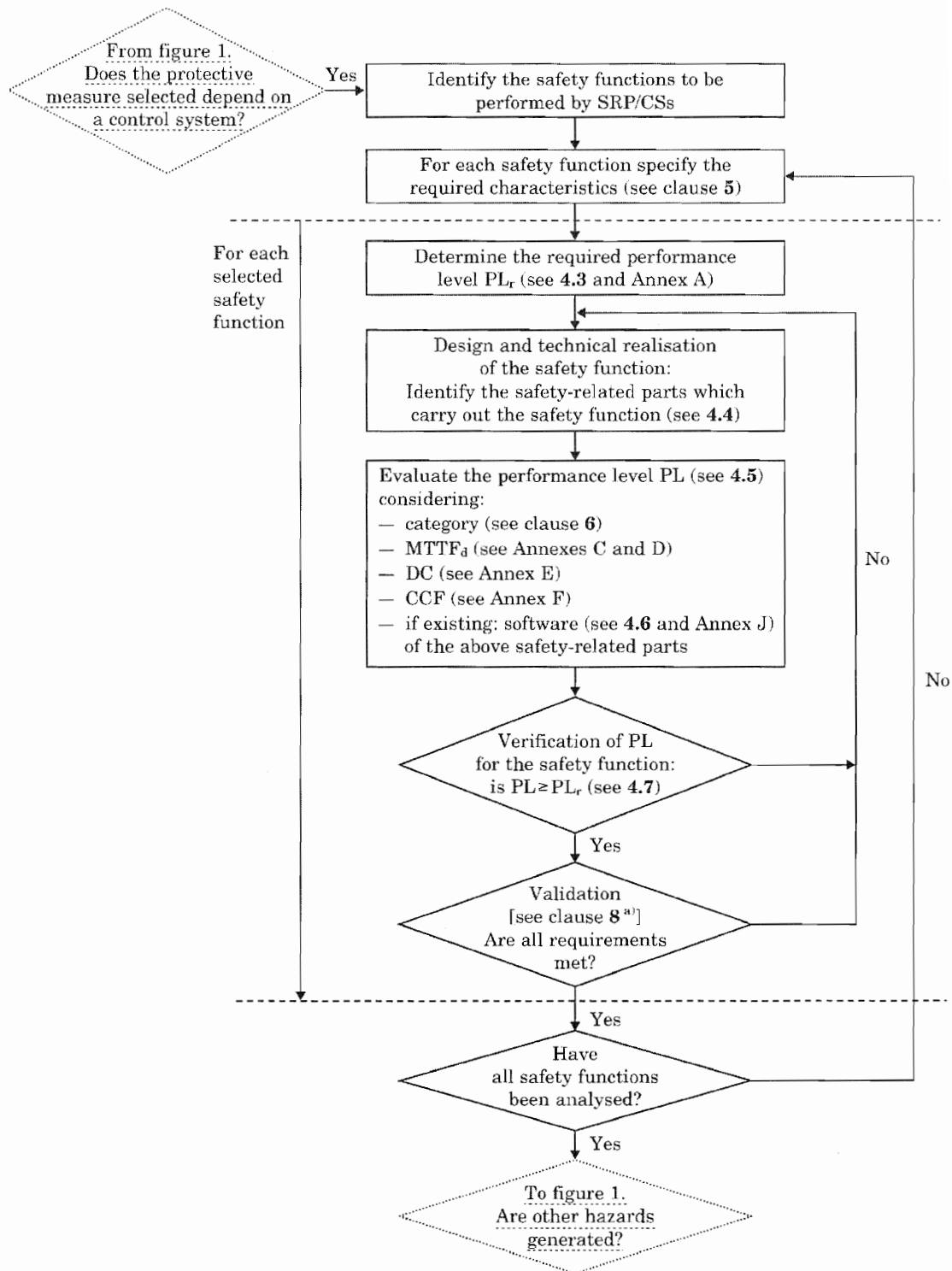
Risk reduction can be achieved by applying various protective measures (both SRP/CS and non SRP/CS) with the end result of achieving a safe condition (see figure 2).



Key

- R_h for a specific hazardous situation, the risk before protective measures are applied
 - R_r risk reduction required from protective measures
 - R_a actual risk reduction achieved with protective measures
 - 1 solution 1 — important part of risk reduction due to protective measures other than SRP/CS (e.g. mechanical measures), small part of risk reduction due to SRP/CS
 - 2 solution 2 — important part of risk reduction due to the SRP/CS (e.g. light curtain), small part of risk reduction due to protective measures other than SRP/CS (e.g. mechanical measures)
 - 3 adequately reduced risk
 - 4 inadequately reduced risk
 - R risk
 - a residual risk obtained by solutions 1 and 2
 - b adequately reduced risk
 - $R1_{SRP/CS}$, $R2_{SRP/CS}$ risk reduction from the safety function carried out by the SRP/CS
 - $R1_M$, $R2_M$ risk reduction from protective measures other than SRP/CS (e.g. mechanical measures)
- NOTE : See JIS B 9700 series for further information on risk reduction.

Figure 2 Overview of the risk reduction process for each hazardous situation



Note ^{a)} ISO 13849-2 provides additional help for the validation.

Figure 3 Iterative process for design of safety-related parts of control systems (SRP/CS)

4.3 Determination of required performance level (PL_r)

For each selected safety function to be carried out by an SRP/CS, a required performance level (PL_r) shall be determined and documented (see Annex A for guidance on determining PL_r). The determination of the required performance level is the result of the risk assessment and refers to the amount of the risk reduction to be carried out by the safety-related parts of the control system (see figure 2).

The greater the amount of risk reduction required to be provided by the SRP/CS, the higher the PL_r shall be.

4.4 Design of SRP/CS

Part of the risk reduction process is to determine the safety functions of the machine. This will include the safety functions of the control system, e.g. prevention of unexpected start-up.

A safety function may be implemented by one or more SRP/CS, and several safety functions may share one or more SRP/CS [e.g. a logic unit, power control element(s)]. It is also possible that one SRP/CS implements safety functions and standard control functions. The designer may use any of the technologies available, singly or in combination. SRP/CS may also provide an operational function (e.g. an AOPD as a means of cycle initiation).

A typical safety function diagrammatic presentation is given in figure 4 showing a combination of safety-related parts of control systems (SRP/CS) for

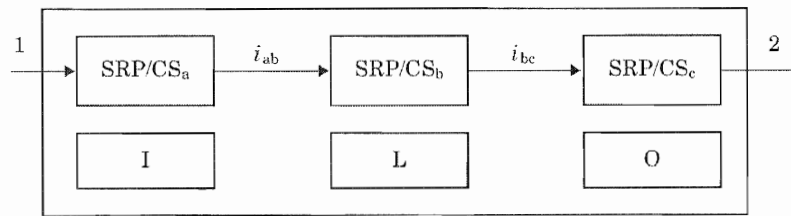
- input (SRP/CS_a),
- logic/processing (SRP/CS_b),
- output/power control elements (SRP/CS_c), and
- interconnecting means (*i*_{ab}, *i*_{bc}) (e.g. electrical, optical).

NOTE 1 Within the same machinery it is important to distinguish between different safety functions and their related SRP/CS carrying out a certain safety function.

Having identified the safety functions of the control system, the designer shall identify the SRP/CS (see figures 1 and 3) and, where necessary, shall assign them to input, logic and output and, in the case of redundancy, the individual channels, and then evaluate the performance level PL (see figure 3).

NOTE 2 Designated architectures are given in clause 6.

NOTE 3 All interconnecting means are included in the safety-related parts.



Key

I input

L logic

O output

1 initiation event (e.g. manual actuation of a push button, opening of guard, interruption of beam of AOPD)

2 machine actuator (e.g. motor brakes)

Figure 4 Diagrammatic presentation of combination of safety-related parts of control systems for processing typical safety function

4.5 Evaluation of the achieved performance level PL and relationship with SIL

4.5.1 Performance level PL

For the purposes of this Standard, the ability of safety-related parts to perform a safety function is expressed through the determination of the performance level.

For each selected SRP/CS and/or for the combination of SRP/CS that performs a safety function the estimation of PL shall be done.

The PL of the SRP/CS shall be determined by the estimation of the following aspects:

- the $MTTF_d$ value for single components (see Annexes C and D);
- the DC (see Annex E);
- the CCF (see Annex F);
- the structure (see clause 6);
- the behaviour of the safety function under fault condition(s) (see clause 6);
- safety-related software (see 4.6 and Annex J);
- systematic failure (see Annex G);
- the ability to perform a safety function under expected environmental conditions.

NOTE 1 Other parameters, e.g. operational aspects, demand rate, test rate, can have certain influence.

These aspects can be grouped under two approaches in relation to the evaluation process:

- a) quantifiable aspects ($MTTF_d$ value for single components, DC, CCF, structure);

- b) non-quantifiable, qualitative aspects which affect the behaviour of the SRP/CS (behaviour of the safety function under fault conditions, safety-related software, systematic failure and environmental conditions).

Among the quantifiable aspects, the contribution of reliability (e.g. MTTF_d, structure) can vary with the technology used. For example, it is possible (within certain limits) for a single channel of safety-related parts of high reliability in one technology to provide the same or higher PL as a fault-tolerant structure of low reliability in another technology.

There are several methods for estimating the quantifiable aspects of the PL for any type of system (e.g. a complex structure), for example, Markov modelling, generalized stochastic petri nets (GSPN), reliability block diagrams (see, e.g. **IEC 61508** series).

To make the assessment of the quantifiable aspects of the PL easier, this Standard provides a simplified method based on the definition of five designated architectures that fulfil specific design criteria and behaviour under a fault condition (see **4.5.4**).

For an SRP/CS or combination of SRP/CS designed according to the requirements given in clause **6**, the average probability of a dangerous failure could be estimated by means of figure 5 and the procedure given in Annexes A to H, J and K.

For an SRP/CS which deviates from the designated architectures, a detailed calculation shall be provided to demonstrate the achievement of the required performance level (PL_r).

In applications where the SRP/CS can be considered simple, and the required performance level is a to c, a qualitative estimation of the PL may be justified in the design rationale.

NOTE 2 For the design of complex control systems, such as PES designed to perform safety functions, the application of other standards can be appropriate (e.g. **IEC 61508** series, **JIS B 9961** or **JIS B 9704** series).

The achievement of qualitative aspects of the PL can be demonstrated by the application of the recommended measures given in **4.6** and Annex G.

In standards in accordance with **IEC 61508** series, the ability of safety-related control systems to perform a safety function is given through a SIL. Table 4 displays the relationship between the two concepts (PLs and SILs).

PLa has no correspondence on the SIL scale and is mainly used to reduce the risk of slight, normally reversible, injury. Since SIL4 is dedicated to catastrophic events possible in the process industry, this range is not relevant for risks at machines. Thus PLe corresponding to SIL3 is defined as the highest level.

Table 4 Relationship between performance level (PL) and safety integrity level (SIL)

PL	SIL high/continuous mode of operation
a	No correspondence
b	1
c	1
d	2
e	3

Therefore, protective measures to reduce the risk shall be applied, principally the following.

- Reduce the probability of faults at the component level. The aim is to reduce the probability of faults or failures which affect the safety function. This can be done by increasing the reliability of components, e.g. by selection of well-tried components and/or applying well-tried safety principles, in order to minimize or exclude critical faults or failures (see **ISO 13849-2**).
- Improve the structure of the SRP/CS. The aim is to avoid the dangerous effect of a fault. Some faults may be detected and a redundant and/or monitored structure could be needed.

Both measures can be applied separately or in combination. With some technologies, risk reduction can be achieved by selecting reliable components and by fault exclusions; but with other technologies, risk reduction could require a redundant and/or monitored system. In addition, common cause failures (CCF) shall be taken into account (see figure 3).

For architectural constraints, see clause 6.

4.5.2 Mean time to dangerous failure of each channel (MTTF_d)

The value of the MTTF_d of each channel is given in three levels (see table 5) and shall be taken into account for each channel (e.g. single channel, each channel of a redundant system) individually.

According to MTTF_d, a maximum value of 100 years can be taken into account.

Table 5 Mean time to dangerous failure of each channel (MTTF_d)

MTTF _d	
Denotation of each channel	Range of each channel
Low	3 years ≤ MTTF _d < 10 years
Medium	10 years ≤ MTTF _d < 30 years
High	30 years ≤ MTTF _d ≤ 100 years
<p>NOTE 1 The choice of the MTTF_d ranges of each channel is based on failure rates found in the field as state-of-the-art, forming a kind of logarithmic scale fitting to the logarithmic PL scale. An MTTF_d value of each channel less than three years is not expected to be found for real SRP/CS since this would mean that after one year about 30 % of all systems on the market will fail and will need to be replaced. An MTTF_d value of each channel greater than 100 years is not acceptable because SRP/CS for high risks should not depend on the reliability of components alone. To reinforce the SRP/CS against systematic and random failure, additional means such as redundancy and testing should be required. To be practicable, the number of ranges was restricted to three. The limitation of MTTF_d of each channel values to a maximum of 100 years refers to the single channel of the SRP/CS which carries out the safety function. Higher MTTF_d values can be used for single components (see table D.1).</p> <p>NOTE 2 The indicated borders of this table are assumed within an accuracy of 5 %.</p>	

For the estimation of MTTF_d of a component, the hierarchical procedure for finding data shall be, in the order given:

- a) use manufacturer's data;
- b) use methods in Annexes C and D;
- c) choose ten years.

4.5.3 Diagnostic coverage (DC)

The value of the DC is given in four levels (see table 6).

For the estimation of DC, in most cases, failure mode and effects analysis (FMEA, see **IEC 60812**) or similar methods can be used. In this case, all relevant faults and/or failure modes should be considered and the PL of the combination of the SRP/CS which carry out the safety function should be checked against the required performance level (PL_r). For a simplified approach to estimating DC, see Annex E.

Table 6 Diagnostic coverage (DC)

DC	
Denotation	Range
None	$DC < 60 \%$
Low	$60 \% \leq DC < 90 \%$
Medium	$90 \% \leq DC < 99 \%$
High	$99 \% \leq DC$
<p>NOTE 1 For SRP/CS consisting of several parts an average value DC_{avg} for DC is used in figure 5, clause 6 and E.2.</p> <p>NOTE 2 The choice of the DC ranges is based on the key values 60 %, 90 % and 99 % also established in other standards (e.g. IEC 61508 series) dealing with diagnostic coverage of tests. Investigations show that $(100 - DC) \%$ rather than DC itself is a characteristic measure for the effectiveness of the test. $(100 - DC) \%$ for the key values 60 %, 90 % and 99 % forms a kind of logarithmic scale fitting to the logarithmic PL-scale. A DC-value less than 60 % has only slight effect on the reliability of the tested system and is therefore called “none”. A DC-value greater than 99 % for complex systems is very hard to achieve. To be practicable, the number of ranges was restricted to four. The indicated borders of this table are assumed within an accuracy of 5 %.</p>	

4.5.4 Simplified procedure for estimating PL

The PL may be estimated by taking into account all relevant parameters and the appropriate methods for calculation (see 4.5.1).

This clause describes a simplified procedure for estimating the PL of an SRP/CS based on designated architectures. Some other architectures with similar structure may be transformed to these designated architectures in order to obtain an estimation of the PL.

The designated architectures are represented as block diagrams, and are listed in the context of each category in 6.2. Information about the block method and the safety-related block diagrams are given in 6.2 and Annex B.

The designated architectures show a logical representation of the system structure for each category. The technical realization or, for example, the functional circuit diagram, may look completely different.

The designated architectures are drawn for the combined SRP/CS, starting at the points where the safety-related signals are initiated and ending at the output of the power control elements (see also JIS B 9700-1, Annex A). The designated architectures can also be used to describe a part of subpart of a control system that responds to input signals and generates safety-related output signals. Thus the “input” element can represent, for example, a light curtain (AOPD) as well as input circuits of control logic elements or input switches. “Output” can also represent, for example, an output signal switching device (OSSD) or outputs of laser-scanners.

For the designated architectures, the following typical assumptions are made:

- mission time, 20 years (see clause 10);
- constant failure rates within the mission time;

- for category 2, demand rate $\leq 1/100$ test rate;
- for category 2, $MTTF_{d,TE}$ larger than half of $MTTF_{d,L}$.

NOTE : When blocks of each channel cannot be separated, the following can be applied: $MTTF_d$ of the summarized test channel (TE, OTE) larger than half $MTTF_d$ of the summarized functional channel (I, L, O).

The methodology considers the categories as architectures with defined DC_{avg} . The PL of each SRP/CS depends on the architecture, the mean time to dangerous failure ($MTTF_d$) in each channel and the DC_{avg} .

Common cause failures (CCF) should also be taken into account (for guidance, see Annex F).

For SRP/CS with software, the requirements of **4.6** apply.

If quantitative data is not available or not used (e.g. low complexity systems), the worst case of all relevant parameters should be chosen.

A combination of SRP/CS or a single SRP/CS may have a PL. The combination of several SRP/CS with different PL is considered in **6.3**.

In the case of applications with PL_r a to c, measures to avoid faults can be sufficient; for higher risk applications, PL_r d to e, the structure of the SRP/CS can provide measures for avoiding, detecting or tolerating faults. Practical measures include redundancy, diversity, monitoring (see also **JIS B 9700-2**, clause **3** and **JIS B 9960-1**).

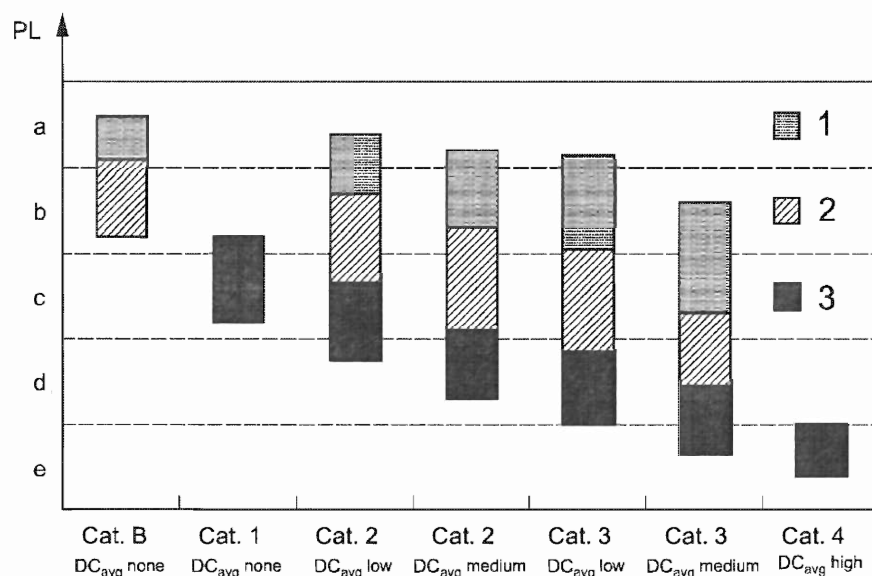
Figure 5 shows the procedure for the selection of categories in combination with the $MTTF_d$ of each channel and DC_{avg} to achieve the required PL of the safety function.

For the estimation of the PL, figure 5 gives the different possible combinations of category with DC_{avg} (horizontal axis) and the $MTTF_d$ of each channel (bars). The bars in the diagram represent the three $MTTF_d$ ranges of each channel (low, medium and high) which can be selected to achieve the required PL.

Before using this simplified approach with figure 5 (which represents results of different Markov models based on designated architectures of clause **6**), the category of the SRP/CS as well as DC_{avg} and the $MTTF_d$ of each channel shall be determined (see clause **6** and Annexes C to E).

For categories 2, 3 and 4, sufficient measures against common cause failure shall be carried out (for guidance, see Annex F). Taking these parameters into account, figure 5 provides a graphical method for determining the PL, achieved by the SRP/CS. The combination of category (including common cause failure) and DC_{avg} determines which column of figure 5 is to be chosen. According to the $MTTF_d$ of each channel, one of the three different shaded areas of the relevant column shall be chosen.

The vertical position of this area determines the achieved PL which can be read off the vertical axis. If the area covers two or three possible PLs, the PL achieved is given in table 7. For a more precise numerical selection of PL depending on the precise value of $MTTF_d$ of each channel, see Annex K.



Key

PL performance level

1 $MTTF_d$ of each channel = low

2 $MTTF_d$ of each channel = medium

3 $MTTF_d$ of each channel = high

Figure 5 Relationship between categories, DC_{avg} , $MTTF_d$ of each channel and PL

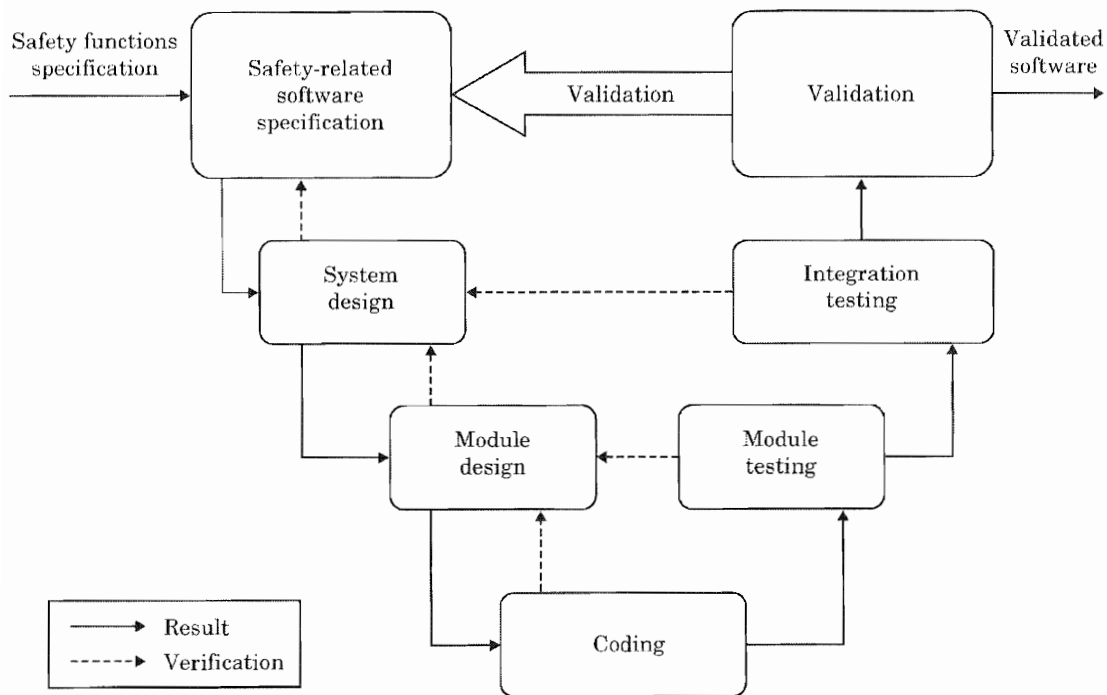
Table 7 Simplified procedure for evaluating PL achieved by SRP/CS

Category	B	1	2	2	3	3	4
DC_{avg}	none	none	low	medium	low	medium	high
$MTTF_d$ of each channel							
Low	a	Not covered	a	b	b	c	Not covered
Medium	b	Not covered	b	c	c	d	Not covered
High	Not covered	c	c	d	d	d	e

4.6 Software safety requirements

4.6.1 General

All lifecycle activities of safety-related embedded or application software shall primarily consider the avoidance of faults introduced during the software lifecycle (see figure 6). The main objective of the following requirements is to have readable, understandable, testable and maintainable software.



NOTE : Annex J gives more detailed recommendations for lifecycle activities.

Figure 6 Simplified V-model of software safety lifecycle

4.6.2 Safety-related embedded software (SRESW)

For SRESW for components with PL_r a to d, the following basic measures shall be applied:

- software safety lifecycle with verification and validation activities, see figure 6;
- documentation of specification and design;
- modular and structured design and coding;
- control of systematic failures (see **G.2**);
- where using software-based measures for control of random hardware failures, verification of correct implementation;
- functional testing, e.g. black box testing;
- appropriate software safety lifecycle activities after modifications.

For SRESW for components with PL_r c or d, the following additional measures shall be applied:

- project management and quality management system comparable to, e.g. **IEC 61508** series or **JIS Q 9001**;
- documentation of all relevant activities during software safety lifecycle;
- configuration management to identify all configuration items and documents related to a SRESW release;

- structured specification with safety requirements and design;
- use of suitable programming languages and computer-based tools with confidence from use;
- modular and structured programming, separation in non-safety-related software, limited module sizes with fully defined interfaces, use of design and coding standards;
- coding verification by walk-through/review with control flow analysis;
- extended functional testing, e.g. grey box testing, performance testing or simulation;
- impact analysis and appropriate software safety lifecycle activities after modifications.

SRESW for components with $PL_r = e$ shall comply with **IEC 61508-3**, clause 7, appropriate for SIL3. When using diversity in specification, design and coding, for the two channels used in SRP/CS with category 3 or 4, $PL_r = e$ can be achieved with the above-mentioned measures for PL_r of c or d.

NOTE 1 For a detailed description of such measures, see, e.g. **IEC 61508-7**.

NOTE 2 For SRESW with diversity in design and coding, for components used in SRP/CS with category 3 or 4, the effort involved in taking measures to avoid systematic failures can be reduced by, for example, reviewing parts of the software only by considering structural aspects instead of checking each line of code.

4.6.3 Safety-related application software (SRASW)

The software safety lifecycle (see figure 6) applies also to SRASW (see Annex J).

SRASW written in LVL and complying with the following requirements can achieve a PL a to e. If SRASW is written in FVL, the requirements for SRESW shall apply and PL a to e is achievable. If a part of the SRASW within one component has any impact (e.g. due to its modification) on several safety functions with different PL, then the requirements related to the highest PL shall apply. For SRASW for components with PL_r from a to e, the following basic measures shall be applied:

- development lifecycle with verification and validation activities, see figure 6;
- documentation of specification and design;
- modular and structured programming;
- functional testing;
- appropriate development activities after modifications.

For SRASW for components with PL_r from c to e, the following additional measures with increasing efficiency (lower effectiveness for PL_r of c, medium effectiveness for PL_r of d, higher effectiveness for PL_r of e) are required or recommended.

- a) The safety-related software specification shall be reviewed (see also Annex J), made available to every person involved in the lifecycle and shall contain the description of:

- 1) safety functions with required PL and associated operation modes,
 - 2) performance criteria, e.g. reaction times,
 - 3) hardware architecture with external signal interfaces, and
 - 4) detection and control of external failure.
- b) Selection of tools, libraries, languages:
- 1) Suitable tools with confidence from use: for PL=e achieved with one component and its tool, the tool shall comply with the appropriate safety standard; if two diverse components with diverse tools are used, confidence from use may be sufficient. Technical features which detect conditions that could cause systematic error (such as data type mismatch, ambiguous dynamic memory allocation, incomplete called interfaces, recursion, pointer arithmetic) shall be used. Checks should mainly be carried out during compile time and not only at runtime. Tools should enforce language subsets and coding guidelines or at least supervise or guide the developer using them.
 - 2) Whenever reasonable and practicable, validated function block (FB) libraries should be used—either safety-related FB libraries provided by the tool manufacturer (highly recommended for PL=e) or validated application specific FB libraries and in conformity with this Standard.
 - 3) A justified LVL-subset suitable for a modular approach should be used, e.g. accepted subset of **JIS B 3503** languages. Graphical languages (e.g. function block diagram, ladder diagram) are highly recommended.
- c) Software design shall feature:
- 1) semi-formal methods to describe data and control flow, e.g. state diagram or program flow chart,
 - 2) modular and structured programming predominantly realized by function blocks deriving from safety-related validated function block libraries,
 - 3) function blocks of limited size of coding,
 - 4) code execution inside function block which should have one entry and one exit point,
 - 5) architecture model of three stages, Inputs \Rightarrow Processing \Rightarrow Outputs (see figure 7 and Annex J),
 - 6) assignment of a safety output at only one program location, and
 - 7) use of techniques for detection of external failure and for defensive programming within input, processing and output blocks which lead to safe state.

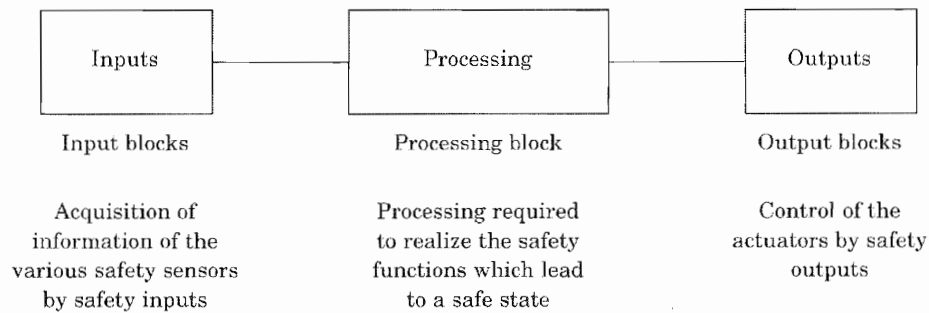


Figure 7 General architecture model of software

- d) Where SRASW and non-SRASW are combined in one component:
- 1) SRASW and non-SRASW shall be coded in different function blocks with well-defined data links;
 - 2) there shall be no logical combination of non-safety-related and safety-related data which could lead to downgrading of the integrity of safety-related signals, for example, combining safety-related and non-safety-related signals by a logical "OR" where the result controls safety-related signals.
- e) Software implementation/coding:
- 1) code shall be readable, understandable and testable and, because of this symbolic variables (instead of explicit hardware addresses) should be used;
 - 2) justified or accepted coding guidelines shall be used (see also Annex J);
 - 3) data integrity and plausibility checks (e.g. range checks) available on application layer (defensive programming) should be used;
 - 4) code should be tested by simulation;
 - 5) verification should be by control and data flow analysis for PL=d or e.
- f) Testing:
- 1) the appropriate validation method is black-box testing of functional behaviour and performance criteria (e.g. timing performance);
 - 2) for PL=d or e, test case execution from boundary value analysis is recommended;
 - 3) test planning is recommended and should include test cases with completion criteria and required tools;
 - 4) I/O testing shall ensure that safety-related signals are correctly used within SRASW.
- g) Documentation:
- 1) all lifecycle and modification activities shall be documented;
 - 2) documentation shall be complete, available, readable and understandable;

- 3) code documentation within source text shall contain module headers with legal entity, functional and I/O description, version and version of used library function blocks, and sufficient comments of networks/statement and declaration lines.
- h) Verification
- Example : Review, inspection, walkthrough or other appropriate activities.
- NOTE : Verification is only necessary for application-specific code, and not for validated library functions.
- i) Configuration management
- It is highly recommended that procedures and data backup be established to identify and archive documents, software modules, verification/validation results and tool configuration related to a specific SRASW version.
- j) Modifications
- After modifications of SRASW, impact analysis shall be performed to ensure specification. Appropriate lifecycle activities shall be performed after modifications. Access rights to modifications shall be controlled and modification history shall be documented.
- NOTE : Modification does not affect systems already in use.

4.6.4 Software-based parameterization

Software-based parameterization of safety-related parameters shall be considered as a safety-related aspect of SRP/CS design to be described in the software safety requirements specification. Parameterization shall be carried out using a dedicated software tool provided by the supplier of the SRP/CS. This tool shall have its own identification (name, version, etc.) and shall prevent unauthorized modification, for example, by use of a password.

The integrity of all data used for parameterization shall be maintained. This shall be achieved by applying measures to

- control the range of valid inputs,
- control data corruption before transmission,
- control the effects of errors from the parameter transmission process,
- control the effects of incomplete parameter transmission, and
- control the effects of faults and failures of hardware and software of the tool used for parameterization.

The parameterization tool shall fulfil all requirements for SRP/CS according to this Standard. Alternatively, a special procedure shall be used for setting the safety-related parameters. This procedure shall include confirmation of input parameters to the SRP/CS by either

- retransmission of the modified parameters to the parameterization tool, or
- other suitable means of confirming the integrity of the parameters,

as well as subsequent confirmation, e.g. by a suitably skilled person and by means of an automatic check by a parameterization tool.

NOTE 1 This is of particular importance where parameterization is carried out using a device not specifically intended for the purpose (e.g. personal computer or equivalent).

The software modules used for encoding/decoding within the transmission/retransmission process and software modules used for visualization of the safety-related parameters to the user shall, as a minimum, use diversity in function(s) to avoid systematic failures.

Documentation of software-based parameterization shall indicate data used (e.g. pre-defined parameter sets) and information necessary to identify the parameters associated with the SRP/CS, the person(s) carrying out the parameterization together with other relevant information such as date of parameterization.

The following verification activities shall be applied for software-based parameterization:

- verification of the correct setting for each safety-related parameter (minimum, maximum and representative values);
- verification that the safety-related parameters are checked for plausibility, for example by use of invalid values, etc.;
- verification that unauthorized modification of safety-related parameters is prevented;
- verification that the data/signals for parameterization are generated and processed in such a way that faults can not lead to a loss of the safety function.

NOTE 2 This is of particular importance where the parameterization is carried out using a device not specifically intended for this purpose (e.g. personal computer or equivalent).

4.7 Verification that achieved PL meets PL_r

For each individual safety function the PL of the related SRP/CS shall match the required performance level (PL_r) determined according to 4.3 (see figure 3). If this is not the case, an iteration in the process described in figure 3 is necessary.

The PL of the different SRP/CS which are part of a safety function shall be greater than or equal to the required performance level (PL_r) of this safety function.

4.8 Ergonomic aspects of design

The interface between operators and the SRP/CS shall be designed and realized such that no person is endangered during all intended use and reasonable foreseeable misuse of the machine (see also **JIS B 9700-2**, **EN 614-1**, **ISO 9355-1**, **ISO 9355-2**, **ISO 9355-3**, **EN 1005-3**, **JIS B 9960-1**, clause 10, **IEC 60447** and **JIS B 9706** series).

Ergonomic principles shall be used so that the machine and the control system, including the safety-related parts, are easy to use, and so that the operator is not tempted to act in a hazardous manner.

The safety requirements for observing ergonomic principles given in **JIS B 9700-2**, 4.8, apply.

5 Safety functions

5.1 Specification of safety functions

This clause provides a list and details of safety functions which can be provided by the SRP/CS. The designer (or type-C standard maker) shall include those necessary to achieve the measures of safety required of the control system for the specific application.

Example : Safety-related stop function, prevention of unexpected start-up, manual reset function, muting function, hold-to-run function.

NOTE : Machinery control systems provide operational and/or safety functions. Operational functions (e.g. starting, normal stopping) can also be safety functions, but this can be ascertained only after a complete risk assessment on the machinery has been carried out.

Tables 8 and 9 list some typical safety functions and, respectively, certain of their characteristics and safety-related parameters, while making reference to other **JISs** and International Standards whose requirements relate to the safety function, characteristic or parameter. The designer (or type-C standard maker) shall ensure that all applicable requirements are satisfied for the relevant safety functions listed in the tables.

Additional requirements are set out in this clause for certain of the safety function characteristics.

Where necessary, the requirements for characteristics and safety functions shall be adapted for use with different energy sources.

As most of the references in tables 8 and 9 relate to electrical standards, the applicable requirements will need to be adapted in the case of other technologies (e.g. hydraulic, pneumatic).

Table 8 Some JISs applicable to typical machine safety functions and certain of their characteristics

Safety function/characteristic	Requirement(s)			For additional information, see:
	This Standard	JIS B 9700-1	JIS B 9700-2	
Safety-related stop function initiated by safeguard ^{a)}	5.2.1	3.26.8	4.11.3	JIS B 9960-1, 9.2.2, 9.2.5.3, 9.2.5.5
Manual reset function	5.2.2	—	—	JIS B 9960-1, 9.2.5.3, 9.2.5.4
Start/restart function	5.2.3	—	4.11.3, 4.11.4	JIS B 9960-1, 9.2.1, 9.2.5.1, 9.2.5.2, 9.2.6
Local control function	5.2.4	—	4.11.8, 4.11.10	JIS B 9960-1, 10.1.5
Muting function	5.2.5	—	—	—
Hold-to-run function	—	—	4.11.8 b)	JIS B 9960-1, 9.2.6.1
Enabling device function	—	—	—	JIS B 9960-1, 9.2.6.3, 10.9
Prevention of unexpected start-up	—	—	4.11.4	JIS B 9714 JIS B 9960-1, 5.4
Escape and rescue of trapped persons	—	—	5.5.3	—
Isolation and energy dissipation function	—	—	5.5.4	JIS B 9714 JIS B 9960-1, 5.3, 6.3.1
Control modes and mode selection	—	—	4.11.8, 4.11.10	JIS B 9960-1, 9.2.3, 9.2.4
Interaction between different safety-related parts of control systems	—	—	4.11.1 (last sentence)	JIS B 9960-1, 9.3.4
Monitoring of parameterization of safety-related input values	4.6.4	—	—	—
Emergency stop function ^{b)}	—	—	5.5.2	JIS B 9703 JIS B 9960-1, 9.2.5.4
Notes ^{a)} Including interlocked guards and limiting devices (e.g. overspeed, overtemperature, overpressure).				
^{b)} Complementary protective measure, see JIS B 9700-1.				

Table 9 Some International Standards and JISs giving requirements for certain safety functions and safety-related parameters

Safety function/ safety-related parameter	Requirement		For additional information, see:
	This Standard	JIS B 9700-2	
Response time	5.2.6	—	JIS B 9715, 3.2, A.3, A.4
Safety-related parameter such as speed, temperature or pressure	5.2.7	4.11.8 e)	JIS B 9960-1, 7.1, 9.3.2, 9.3.4
Fluctuations, loss and restoration of power sources	5.2.8	4.11.8 e)	JIS B 9960-1, 4.3, 7.1, 7.5
Indications and alarms	—	4.8	ISO 7731 ISO 11428 ISO 11429 JIS B 9706-1 JIS B 9960-1, 10.3, 10.4 IEC 61131 series JIS B 9961

When identifying and specifying the safety function(s), the following shall at least be considered:

- a) results of the risk assessment for each specific hazard or hazardous situation;
- b) machine operating characteristics, including
 - intended use of the machine (including reasonable foreseeable misuse),
 - modes of operation (e.g. local mode, automatic mode, modes related to a zone or part of the machine),
 - cycle time, and
 - response time;
- c) emergency operation;
- d) description of the interaction of different working processes and manual activities (repairing, setting, cleaning, trouble shooting, etc.);
- e) the behaviour of the machine that a safety function is intended to achieve or to prevent;
- f) condition(s) (e.g. operating mode) of the machine in which it is to be active or disabled;
- g) the frequency of operation;
- h) priority of those functions that can be simultaneously active and that can cause conflicting action.

5.2 Details of safety functions

5.2.1 Safety-related stop function

The following applies in addition to the requirements of table 8.

A safety-related stop function (e.g. initiated by a safeguard) shall, as soon as necessary after actuation, put the machine in a safe state. Such a stop shall have priority over a stop for operational reasons.

When a group of machines are working together in a coordinated manner, provision shall be made for signalling the supervisory control and/or the other machines that such a stop condition exists.

NOTE : A safety-related stop function can cause operational problems and a difficult restart, e.g. in an arc welding application. To reduce the temptation to defeat this stop function, it can be preceded with a stop for operational reasons to finalize the actual operation and prepare for an easy and quick restart from the stop position (e.g. without any damage of the production). One solution is the use of interlocking device with guard locking where the guard locking is released when the cycle has reached a defined position where the easy restart is possible.

5.2.2 Manual reset function

The following applies in addition to the requirements of table 8.

After a stop command has been initiated by a safeguard, the stop condition shall be maintained until safe conditions for restarting exist.

The re-establishment of the safety function by resetting of the safeguard cancels the stop command. If indicated by the risk assessment, this cancellation of the stop command shall be confirmed by a manual, separate and deliberate action (manual reset).

The manual reset function shall

- be provided through a separate and manually operated device within the SRP/CS,
- only be achieved if all safety functions and safeguards are operative,
- not initiate motion or a hazardous situation by itself,
- be by deliberate action,
- enable the control system for accepting a separate start command,
- only be accepted by disengaging the actuator from its energized (on) position.

The performance level of safety-related parts providing the manual reset function shall be selected so that the inclusion of the manual reset function does not diminish the safety required of the relevant safety function.

The reset actuator shall be situated outside the danger zone and in a safe position from which there is good visibility for checking that no person is within the danger zone.

Where the visibility of the danger zone is not complete, a special reset procedure is required.

NOTE : One solution is the use of a second reset actuator. The reset function is initiated within the danger zone by the first actuator in combination with a second reset actuator located outside the danger zone (near the safeguard). This reset procedure needs to be realized within a limited time before the control system accepts a separate start command.

5.2.3 Start/restart function

The following applies in addition to the requirements of table 8.

A restart shall take place automatically only if a hazardous situation cannot exist. In particular, for interlocking guards with a start function, **JIS B 9700-2, 5.3.2.5**, applies.

These requirements for start and restart shall also apply to machines which can be controlled remotely.

NOTE : A sensor feedback signal to the control system can initiate an automatic restart.

Example : In automatic machine operations, sensor feedback signals to the control system are often used to control the process flow. If a work piece has come out of position, the process flow is stopped. If the monitoring of the interlocked safeguard is not superior to the automatic process control, there could be a danger of restarting the machine while the operator readjusts the work piece. Therefore the remotely controlled restart ought not to be allowed until the safeguard is closed again and the maintainer has left the hazardous area. The contribution of prevention of unexpected start-up provided by the control system is dependent on the result of the risk assessment.

5.2.4 Local control function

The following applies in addition to the requirements of table 8.

When a machine is controlled locally, e.g. by a portable control device or pendant, the following requirements shall apply:

- the means for selecting local control shall be situated outside the danger zone;
- it shall only be possible to initiate hazardous conditions by a local control in a zone defined by the risk assessment;
- switching between local and main control shall not create a hazardous situation.

5.2.5 Muting function

The following applies in addition to the requirements of table 8.

Muting shall not result in any person being exposed to hazardous situations. During muting, safe conditions shall be provided by other means.

At the end of muting, all safety functions of the SRP/CS shall be reinstated.

The performance level of safety-related parts providing the muting function shall be selected so that the inclusion of the muting function does not diminish the safety required of the relevant safety function.

NOTE : In some applications, an indication signal of muting is necessary.

5.2.6 Response time

The following applies in addition to the requirements of table 9.

The response time of the SRP/CS shall be determined when the risk assessment of the SRP/CS indicates that this is necessary (see also clause 11).

NOTE : The response time of the control system is part of the overall response time of the machine. The required overall response time of the machine can influence the design of the safety-related part, e.g. the need to provide a braking system.

5.2.7 Safety-related parameters

The following applies in addition to the requirements of table 9.

When safety-related parameters, e.g. position, speed, temperature or pressure, deviate from present limits the control system shall initiate appropriate measures (e.g. actuation of stopping, warning signal, alarm).

If errors in manual inputting of safety-related data in programmable electronic systems can lead to a hazardous situation, then a data checking system within the safety-related control system shall be provided, e.g. check of limits, format and/or logic input values.

5.2.8 Fluctuations, loss and restoration of power sources

The following applies in addition to the requirements of table 9.

When fluctuations in energy levels outside the design operating range occur, including loss of energy supply, the SRP/CS shall continue to provide or initiate output signal(s) which will enable other parts of the machine system to maintain a safe state.

6 Categories and their relation to $MTTF_d$ of each channel, DC_{avg} and CCF

6.1 General

The SRP/CS shall be in accordance with the requirements of one or more of the five categories specified in **6.2**.

Categories are the basic parameters used to achieve a specific PL. They state the required behaviour of the SRP/CS in respect of its resistance to faults based on the design considerations described in clause 4.

Category B is the basic category. The occurrence of a fault can lead to the loss of the safety function. In category 1 improved resistance to faults is achieved predominantly by selection and application of components. In categories 2, 3 and 4, improved performance in respect of a specified safety function is achieved predominantly by improving the structure of the SRP/CS. In category 2 this is provided by periodically checking that the specified safety function is being performed. In categories 3 and 4 this is provided by ensuring that the single fault will not lead to the loss of the safety function. In category 4, and whenever reasonably practicable in category 3, such faults will be detected. In category 4 the resistance to the accumulation of faults will be specified.

Table 10 gives an overview of categories of the SRP/CS, the requirements and the system behaviour in case of faults.

When considering the causes of failures in some components it is possible to exclude certain faults (see clause 7).

The selection of a category for a particular SRP/CS depends mainly upon

- the reduction in risk to be achieved by the safety function to which the part contributes,
- the required performance level (PL_r),
- the technologies used,
- the risk arising in the case of a fault(s) in that part,
- the possibilities of avoiding a fault(s) in that part (systematic faults),
- the probability of occurrence of a fault(s) in that part and relevant parameters,
- the mean time to dangerous failure ($MTTF_d$),
- the diagnostic coverage (DC), and
- the common cause failure (CCF) in the case of categories 2, 3 and 4.

6.2 Specifications of categories

6.2.1 General

Each SRP/CS shall comply with the requirements of the relevant category, see **6.2.3** to **6.2.7**.

The following architectures typically meet the requirements of the respective category.

The following figures 8 to 12 show not examples but general architectures. A deviation from these architectures is always possible, but any deviation shall be justified, by means of appropriate analytical tools (e.g. Markov modelling, fault tree analysis), such that the system meets the required performance level (PL_r).

The designated architectures cannot be considered only as circuit diagrams but also as logical diagrams. For categories 3 and 4, this means that not all parts are necessarily physically redundant but that there are redundant means of assuring that a fault cannot lead to the loss of the safety function.

The lines and arrows in figures 8 to 12 represent logical interconnecting means and logical possible diagnostic means.

6.2.2 Designated architectures

The structure of an SRP/CS is a key characteristic having great influence on the PL. Even if the variety of possible structures is high, the basic concepts are often similar. Thus, most structures which are present in the machinery field can be mapped to one of the categories. For each category, a typical representation as a safety-related block diagram can be made. These typical realizations are called designated architectures and are listed in the context of each of the following categories (see figures 8 to 12).

It is important that the PL shown in figure 5, depending on the category, $MTTF_d$ of each channel and DC_{avg} , is based on the designated architectures. If figure 5 is used to estimate the PL the architecture of the SRP/CS should be demonstrated to be equivalent to the designated architecture of the claimed category. Designs fulfilling the characteristics of the respective category in general are equivalent to the respective designated architecture of the category.

NOTE : In some cases arising from a specific technical solution or determined by a type-C standard, the safety-related performance of the SRP/CS can be required only by a category without additional PL_r . For such specific cases, safety is provided particularly by the architecture, and the requirements for MTTF, DC and CCF do not apply.

6.2.3 Category B

The SRP/CS shall, as a minimum, be designed, constructed, selected, assembled and combined in accordance with the relevant standards and using basic safety principles for the specific application to withstand

- the expected operating stresses, e.g. the reliability with respect to breaking capacity and frequency,
- the influence of the processed material, e.g. detergents in a washing machine, and
- other relevant external influences, e.g. mechanical vibration, electromagnetic interference, power supply interruptions or disturbances.

There is no diagnostic coverage ($DC_{avg} = \text{none}$) within category B systems and the $MTTF_d$ of each channel can be low to medium. In such structures (normally single-channel systems), the consideration of CCF is not relevant.

The maximum PL achievable with category B is $PL = b$.

NOTE : When a fault occurs it can lead to the loss of the safety function.

Specific requirements for electromagnetic compatibility are found in the relevant product standards, e.g. **JIS C 4421** for power drive systems. For functional safety of SRP/CS in particular, the immunity requirements are relevant. If no product standard exists, at least the immunity requirements of **JIS C 61000-6-2** should be followed.

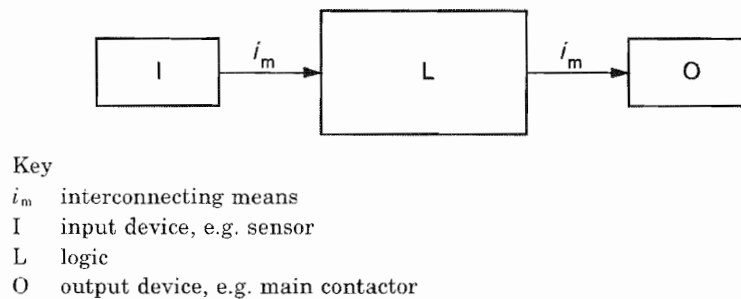


Figure 8 Designated architecture for category B

6.2.4 Category 1

For category 1, the same requirements as those according to **6.2.3** for category B shall apply. In addition, the following applies.

SRP/CS of category 1 shall be designed and constructed using well-trying components and well-trying safety principles (see **ISO 13849-2**).

A “well-trying component” for a safety-related application is a component which has been either

- a) widely used in the past with successful results in similar applications, or
- b) made and verified using principles which demonstrate its suitability and reliability for safety-related applications.

Newly developed components and safety principles may be considered as equivalent to “well-tried” if they fulfil the conditions of **b**).

The decision to accept a particular component as being “well-tried” depends on the application.

NOTE 1 Complex electronic components (e.g. PLC, microprocessor, application-specific integrated circuit) cannot be considered as equivalent to “well-tried”.

The $MTTF_d$ of each channel shall be high.

The maximum PL achievable with category 1 is $PL = c$.

NOTE 2 There is no diagnostic coverage ($DC_{avg} = \text{none}$) within category 1 systems. In such structures (single-channel systems) the consideration of CCF is not relevant.

NOTE 3 When a fault occurs it can lead to the loss of the safety function. However, the $MTTF_d$ of each channel in category 1 is higher than in category B. Consequently, the loss of the safety function is less likely.

It is important that a clear distinction between “well-tried component” and “fault exclusion” (see clause 7) be made. The qualification of a component as being well-tried depends on its application. For example, a position switch with positive opening contacts could be considered as being well-tried for a machine tool, while at the same time as being inappropriate for application in a food industry — in the milk industry, for instance, this switch would be destroyed by the milk acid after a few months. A fault exclusion can lead to a very high PL, but the appropriate measures to allow this fault exclusion should be applied during the whole lifetime of the device. In order to ensure this, additional measures outside the control system may be necessary. In the case of a position switch, some examples of these kinds of measures are

- means to secure the fixing of the switch after its adjustment,
- means to secure the fixing of the cam,
- means to ensure the transverse stability of the cam,
- means to avoid overtravel of the position switch, e.g. adequate mounting strength of the shock absorber and any alignment devices, and
- means to protect it against damage from outside.

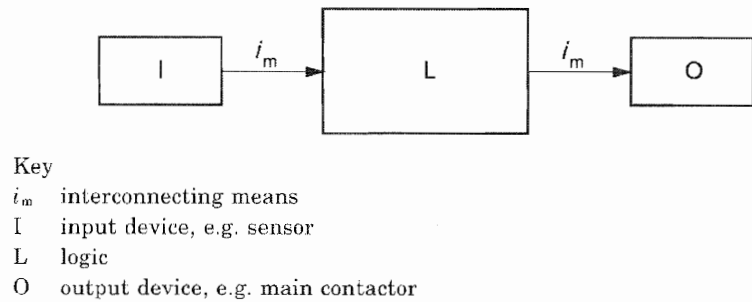


Figure 9 Designated architecture for category 1

6.2.5 Category 2

For category 2, the same requirements as those according to 6.2.3 for category B shall apply. “Well-tries safety principles” according to 6.2.4 shall also be followed. In addition, the following applies.

SRP/CS of category 2 shall be designed so that their function(s) are checked at suitable intervals by the machine control system. The check of the safety function(s) shall be performed

- at the machine start-up, and
- prior to the initiation of any hazardous situation, e.g. start of a new cycle, start of other movements, and/or periodically during operation if the risk assessment and the kind of operation shows that it is necessary.

The initiation of this check may be automatic. Any check of the safety function(s) shall either

- allow operation if no faults have been detected, or
- generate an output which initiates appropriate control action, if a fault is detected.

Whenever possible this output shall initiate a safe state. This safe state shall be maintained until the fault is cleared. When it is not possible to initiate a safe state (e.g. welding of the contact in the final switching device) the output shall provide a warning of the hazard.

For the designated architecture of category 2, as shown in figure 10, the calculation of $MTTF_d$ and DC_{avg} should take into account only the blocks of the functional channel (i.e. I, L and O in figure 10) and not the blocks of the testing channel (i.e. TE and OTE in figure 10).

The diagnostic coverage (DC_{avg}) of the total SRP/CS including fault-detection shall be low to medium. The $MTTF_d$ of each channel shall be low-to-high, depending on the required performance level (PL_r). Measures against CCF shall be applied (see Annex F).

The check itself shall not lead to a hazardous situation (e.g. due to an increase in response time). The checking equipment may be integral with, or separate from, the safety-related part(s) providing the safety function.

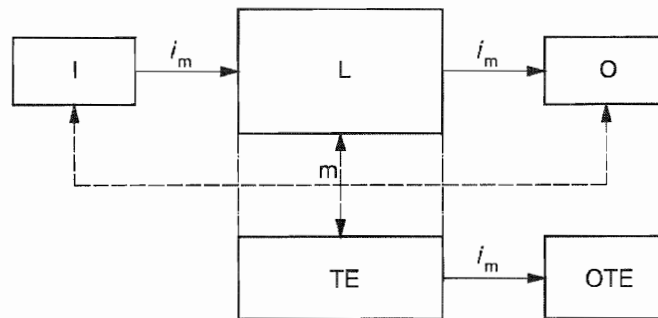
The maximum PL achievable with category 2 is $PL=d$.

NOTE 1 In some cases category 2 is not applicable because the checking of the safety function cannot be applied to all components.

NOTE 2 Category 2 system behaviour allows that

- the occurrence of a fault can lead to the loss of the safety function between checks,
- the loss of safety function is detected by the check.

NOTE 3 The principle that supports the validity of a category 2 function is that the adopted technical provisions, and, for example, the choice of checking frequency can decrease the probability of occurrence of a dangerous situation.



Dashed lines represent reasonably practicable fault detection.

Key

- i_m interconnecting means
- I input device, e.g. sensor
- L logic
- m monitoring
- O output device, e.g. main contactor
- TE test equipment
- OTE output of TE

Figure 10 Designated architecture for category 2

6.2.6 Category 3

For category 3, the same requirements as those according to 6.2.3 for category B shall apply. “Well-trying safety principles” according to 6.2.4 shall also be followed. In addition, the following applies.

SRP/CS of category 3 shall be designed so that a single fault in any of these parts does not lead to the loss of the safety function. Whenever reasonably practicable, the single fault shall be detected at or before the next demand upon the safety function.

The diagnostic coverage (DC_{avg}) of the total SRP/CS including fault-detection shall be low to medium. The $MTTF_d$ of each of the redundant channels shall be low-to-high, depending on the PL_r . Measures against CCF shall be applied (see Annex F).

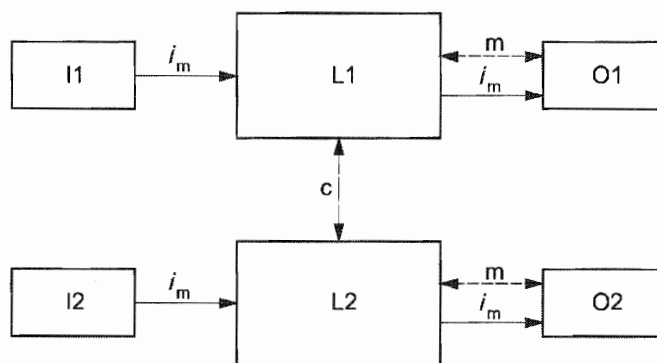
NOTE 1 The requirement of single-fault detection does not mean that all faults will be detected. Consequently, the accumulation of undetected faults can lead to an unintended output and a hazardous situation at the machine. Typical examples of practicable measures for fault detection are use of the feedback of mechanically guided relay contacts and monitoring of redundant electrical outputs.

NOTE 2 If necessary because of technology and application, type-C standard makers need to give further details on the detection of faults.

NOTE 3 Category 3 system behaviour allows that

- when the single fault occurs the safety function is always performed,
- some but not all faults will be detected,
- accumulation of undetected faults can lead to the loss of the safety function.

NOTE 4 The technology used will influence the possibilities for the implementation of fault detection.



Dashed lines represent reasonably practicable fault detection.

Key

- i_m interconnecting means
- c cross monitoring
- I1, I2 input device, e.g. sensor
- L1, L2 logic
- m monitoring
- O1, O2 output device, e.g. main contactor

Figure 11 Designated architecture for category 3

6.2.7 Category 4

For category 4, the same requirements as those according to 6.2.3 for category B shall apply. “Well-tried safety principles” according to 6.2.4 shall also be followed. In addition, the following applies.

SRP/CS of category 4 shall be designed such that

- a single fault in any of these safety-related parts does not lead to a loss of the safety function, and
- the single fault is detected at or before the next demand upon the safety functions, e.g. immediately, at switch on, or at end of a machine operating cycle,

but if this detection is not possible, then an accumulation of undetected faults shall not lead to the loss of the safety function.

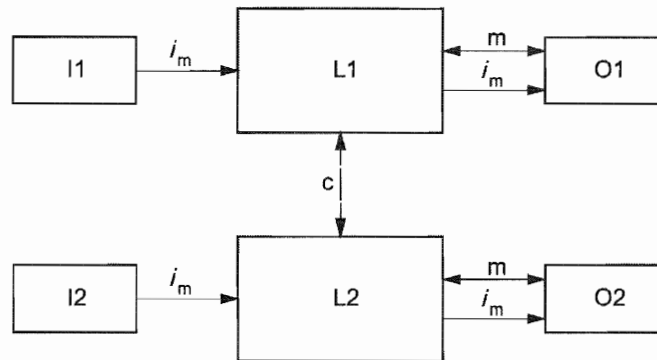
The diagnostic coverage (DC_{avg}) of the total SRP/CS shall be high, including the accumulation of faults. The $MTTF_d$ of each of the redundant channels shall be high. Measures against CCF shall be applied (see Annex F).

NOTE 1 Category 4 system behaviour allows that

- when a single fault occurs the safety function is always performed,
- the faults will be detected in time to prevent the loss of the safety function,
- accumulation of undetected faults is taken into account.

NOTE 2 The difference between category 3 and category 4 is a higher DC_{avg} in category 4 and a required $MTTF_d$ of each channel of “high” only.

In practice, the consideration of a fault combination of two faults may be sufficient.



Solid lines for monitoring represent diagnostic coverage that is higher than in the designated architecture for category 3.

Key

- i_m interconnecting means
- c cross monitoring
- I1, I2 input device, e.g. sensor
- L1, L2 logic
- m monitoring
- O1, O2 output device, e.g. main contactor

Figure 12 Designated architecture for category 4

Table 10 Summary of requirements for categories

Category	Summary of requirements	System behaviour	Principle used to achieve safety	MTTF _d of each channel	DC _{avg}	CCF
B (see 6.2.3)	SRP/CS and/or their protective equipment, as well as their components, shall be designed, constructed, selected, assembled and combined in accordance with relevant standards so that they can withstand the expected influence. Basic safety principles shall be used.	The occurrence of a fault can lead to the loss of the safety function.	Mainly characterized by selection of components	Low to medium	None	Not relevant
1 (see 6.2.4)	Requirements of B shall apply. Well-tried components and well-tried safety principles shall be used.	The occurrence of a fault can lead to the loss of the safety function but the probability of occurrence is lower than for category B.	Mainly characterized by selection of components	High	None	Not relevant
2 (see 6.2.5)	Requirements of B and the use of well-tried safety principles shall apply. Safety function shall be checked at suitable intervals by the machine control system.	The occurrence of a fault can lead to the loss of the safety function between the checks. The loss of safety function is detected by the check.	Mainly characterized by structure	Low to high	Low to medium	See Annex F
3 (see 6.2.6)	Requirements of B and the use of well-tried safety principles shall apply. Safety-related parts shall be designed, so that – a single fault in any of these parts does not lead to the loss of the safety function, and – whenever reasonably practicable, the single fault is detected.	When a single fault occurs, the safety function is always performed. Some, but not all, faults will be detected. Accumulation of undetected faults can lead to the loss of the safety function.	Mainly characterized by structure	Low to high	Low to medium	See Annex F

Table 10 (concluded)

Category	Summary of requirements	System behaviour	Principle used to achieve safety	MTTF _d of each channel	DC _{avg}	CCF
4 (see 6.2.7)	Requirements of B and the use of well-tried safety principles shall apply. Safety-related parts shall be designed, so that <ul style="list-style-type: none"> – a single fault in any of these parts does not lead to a loss of the safety function, and – the single fault is detected at or before the next demand upon the safety function, but that if this detection is not possible, an accumulation of undetected faults shall not lead to the loss of the safety function. 	When a single fault occurs the safety function is always performed. Detection of accumulated faults reduces the probability of the loss of the safety function (high DC). The faults will be detected in time to prevent the loss of the safety function.	Mainly characterized by structure	High	High including accumulation of faults	See Annex F
NOTE : For full requirements, see clause 6.						

6.3 Combination of SRP/CS to achieve overall PL

A safety function can be realized by a combination of several SRP/CS: input system, signal processing unit, output system. These SRP/CS may be assigned to one and/or different categories. For each SRP/CS used, a category according to 6.2 shall be selected. For the overall combination of these SRP/CS, an overall PL may be identified using table 11. In this case, the validation of the combination of SRP/CS is required (see figure 3).

According to 6.2, the combined safety-related parts of a control system start at the points where the safety-related signals are initiated and end at the output of the power control elements. But the combined SRP/CS could consist of several parts connected in a linear (series alignment) or redundant (parallel alignment) way. To avoid a new complex estimation of the performance level (PL) achieved by the combined SRP/CS where the separate PLs of all parts are already calculated, the following estimations are presented for a series alignment of SRP/CS.

Assumed are N separate SRP/CS_{*i*} in a series alignment, as a whole performing a safety function. For each SRP/CS_{*i*}, a PL_{*i*} has already been evaluated. This situation is illustrated in figure 13 (see also figure 4 and figure H.2).

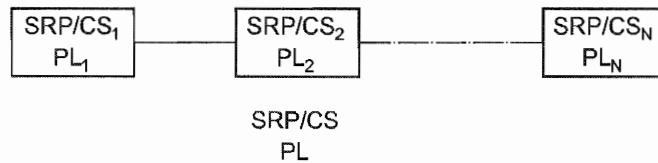


Figure 13 Combination of SRP/CS to achieve overall PL

The following method allows the calculation of the PL of the whole combined SRP/CS performing the safety function:

- Identify the lowest PL_i : this is PL_{low} .
- Identify the number $N_{low} \leq N$ of SRP/CS_i , with $PL_i = PL_{low}$.
- Look-up PL in table 11.

Table 11 Calculation of PL for series alignment of SRP/CS

PL_{low}	N_{low}	\Rightarrow	PL
a	> 3	\Rightarrow	None, not allowed
	≤ 3	\Rightarrow	a
b	> 2	\Rightarrow	a
	≤ 2	\Rightarrow	b
c	> 2	\Rightarrow	b
	≤ 2	\Rightarrow	c
d	> 3	\Rightarrow	c
	≤ 3	\Rightarrow	d
e	> 3	\Rightarrow	d
	≤ 3	\Rightarrow	e
NOTE : The values calculated for this look-up table are based on reliability values at the mid-point for each PL.			

7 Fault consideration, fault exclusion

7.1 General

In accordance with the category selected, safety-related parts shall be designed to achieve the required performance level (PL_r). The ability to resist faults shall be assessed.

7.2 Fault consideration

ISO 13849-2 lists the important faults and failures for the various technologies. The lists of faults are not exclusive and, if necessary, additional faults shall be considered and listed. In such cases, the method of evaluation should also be clearly elaborated. For new components not mentioned in **ISO 13849-2**, a failure mode and effects analysis (FMEA, see **IEC 60812**) shall be carried out to establish the faults that are to be considered for those components.

In general, the following fault criteria shall be taken into account:

- if, as a consequence of a fault, further components fail, the first fault together with all following faults shall be considered as a single fault;
- two or more separate faults having a common cause shall be considered as a single fault (known as a CCF);
- the simultaneous occurrence of two or more faults having separate causes is considered highly unlikely and therefore need not be considered.

7.3 Fault exclusion

It is not always possible to evaluate SRP/CS without assuming that certain faults can be excluded. For detailed information on fault exclusions, see **ISO 13849-2**.

Fault exclusion is a compromise between technical safety requirements and the theoretical possibility of occurrence of a fault.

Fault exclusion can be based on

- the technical improbability of occurrence of some faults,
- generally accepted technical experience, independent of the considered application, and
- technical requirements related to the application and the specific hazard.

If faults are excluded, a detailed justification shall be given in the technical documentation.

8 Validation

The design of the SRP/CS shall be validated (see figure 3). The validation shall demonstrate that the combination of SRP/CS providing each safety function meets all relevant requirements of this Standard.

For details of validation, see **ISO 13849-2**.

9 Maintenance

Preventive or corrective maintenance can be necessary to maintain the specified performance of the safety-related parts. Deviations with time from the specified performance can lead to a deterioration in safety or even to a hazardous situation. The information for use of the SRP/CS shall include instructions for the maintenance (including periodic inspection) of the SRP/CS.

The provisions for the maintainability of the safety-related part(s) of a control system shall follow the principles given in **JIS B 9700-2, 4.7**. All information for maintenance shall comply with **JIS B 9700-2, 6.5.1 e**).

10 Technical documentation

When designing an SRP/CS, its designer shall document at least the following information relevant to the safety-related part:

- safety function(s) provided by the SRP/CS;
- the characteristics of each safety function;

- the exact points at which the safety-related part(s) start and end;
- environmental conditions;
- the performance level (PL);
- the category or categories selected;
- the parameters relevant to the reliability (MTTF_a, DC, CCF and mission time);
- measures against systematic failure;
- the technology or technologies used;
- all safety-relevant faults considered;
- justification for fault exclusions (see **ISO 13849-2**);
- the design rationale (e.g. faults considered, faults excluded);
- software documentation;
- measures against reasonably foreseeable misuse.

NOTE : In general, this documentation is foreseen as being for the manufacturer's internal purposes and will not be distributed to the machine user.

11 Information for use

The principles of **JIS B 9700-2**, **6.5.2**, and the applicable sections of other relevant documents (e.g. **JIS B 9960-1**, clause **17**), shall be applied. In particular, that information which is important for the safe use of the SRP/CS shall be given to the user. This shall include, but is not limited to the following:

- the limits of the safety-related parts to the category(ies) selected and any fault exclusions;
- the limits of the SRP/CS and any fault exclusions (see **7.3**), for which, when essential for maintaining the selected category or categories and safety performance, appropriate information (e.g. for modification, maintenance and repair) shall be given to ensure the continued justification of the fault exclusion(s);
- the effects of deviations from the specified performance on the safety function(s);
- clear descriptions of the interfaces to the SRP/CS and protective devices;
- response time;
- operating limits (including environmental conditions);
- indications and alarms;
- muting and suspension of safety functions;
- control modes;
- maintenance (see clause **9**);
- maintenance check lists;
- ease of accessibility and replacing of internal parts;
- means for easy and safe trouble shooting;

- information explaining the applications for use relevant to the category to which reference is made;
- checking test intervals where relevant.

Specific information shall be provided on the category or categories and performance level of the SRP/CS, as follows:

- dated reference to this Standard (i.e. “**JIS B 9705-1:2011**”);
- the Category, B, 1, 2, 3, or 4;
- the performance level, a, b, c, d, or e.

Example : An SRP/CS in accordance with this Standard, of Category B and performance level a, would be referred to as follows:

JIS B 9705-1:2011 Category B PL a

Annex A (informative)

Determination of required performance level (PL_r)

A.1 Selection of PL_r

This Annex is concerned with the contribution to the reduction in risk made by the safety-related parts of the control system being considered. The method given here provides only an estimation of risk reduction and is intended as guidance to the designer and standard maker in determining the PL_r for each necessary safety function to be carried out by an SRP/CS.

The risk assessment assumes a situation prior to provision of the intended safety function. Risk reduction by other technical measures independent of the control system (e.g. mechanical guards), or additional safety functions, can be taken into account in determining the PL_r of the intended safety function; in which case, the starting point of figure A.1 can be selected after the implementation of these measures (see also figure 2). The severity of injury (denoted by S) is relatively easy to estimate (e.g. laceration, amputation, fatality). For the frequency of occurrence, auxiliary parameters are used to improve the estimation. These parameters are

- frequency and time of exposure to the hazard (F), and
- possibility of avoiding the hazard or limiting the harm (P).

Experience has shown that these parameters can be combined, as in figure A.1, to give a gradation of risk from low to high. It is emphasized that this is a qualitative process giving only an estimation of risk.

A.2 Guidance for selecting parameters S, F and P for the risk estimation

A.2.1 Severity of injury S1 and S2

In estimating the risk arising from a failure of a safety function only slight injuries (normally reversible) and serious injuries (normally irreversible) and death are considered.

To make a decision the usual consequences of accidents and normal healing processes should be taken into account in determining S1 and S2. For example, bruising and/or lacerations without complications would be classified as S1, whereas amputation or death would be S2.

A.2.2 Frequency and/or exposure times to hazard, F1 and F2

A generally valid time period to be selected for parameter F1 or F2 cannot be specified. However, the following explanation could facilitate making the right decision where doubt exists.

F2 should be selected if a person is frequently or continuously exposed to the hazard. It is irrelevant whether the same or different persons are exposed to the hazard on successive exposures, e.g. for the use of lifts. The frequency parameter should be chosen according to the frequency and duration of access to the hazard.

Where the demand on the safety function is known by the designer, the frequency and duration of this demand can be chosen instead of the frequency and duration of access to the hazard. In this Standard, the frequency of demand on the safety function is assumed to be more than once per year.

The period of exposure to the hazard should be evaluated on the basis of an average value which can be seen in relation to the total period of time over which the equipment is used. For example, if it is necessary to reach regularly between the tools of the machine during cyclic operation in order to feed and move work pieces, then F2 should be selected. If access is only required from time to time, then F1 should be selected.

NOTE : In case of no other justification F2 should be chosen, if the frequency is higher than once per hour.

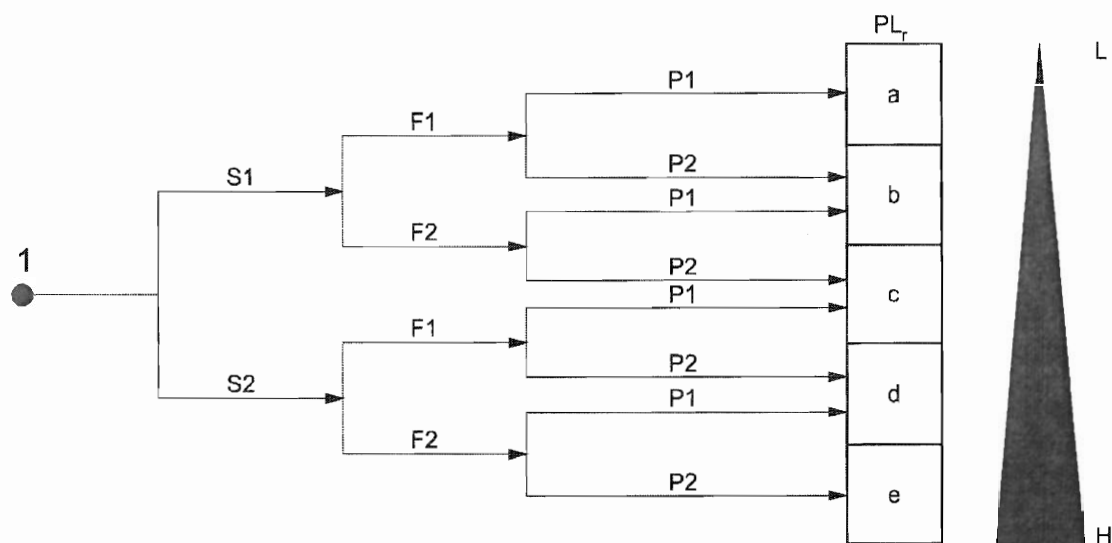
A.2.3 Possibility of avoiding the hazard P1 and P2

It is important to know whether a hazardous situation can be recognized and avoided before leading to an accident. For example, an important consideration is whether the hazard can be directly identified by its physical characteristics, or recognized only by technical means, e.g. indicators. Other important aspects which influence the selection of parameter P include, for example:

- operation with or without supervision;
- operation by experts or non-professionals;
- speed with which the hazard arises (e.g. quickly or slowly);
- possibilities for hazard avoidance (e.g. by escaping);
- practical safety experiences relating to the process.

When a hazardous situation occurs, P1 should only be selected if there is a realistic chance of avoiding an accident or of significantly reducing its effect; P2 should be selected if there is almost no chance of avoiding the hazard.

Figure A.1 provides guidance for the determination of the safety-related PL_r depending on the risk assessment. The graph should be considered for each safety function. The risk assessment method is based on **JIS B 9702** and should be used in accordance with **JIS B 9700-1**.



Key

- 1 starting point for evaluation of safety function's contribution to risk reduction
- L low contribution to risk reduction
- H high contribution to risk reduction
- PL_r required performance level

Risk parameters:

- S severity of injury
- S1 slight (normally reversible injury)
- S2 serious (normally irreversible injury or death)
- F frequency and/or exposure to hazard
- F1 seldom-to-less-often and/or exposure time is short
- F2 frequent-to-continuous and/or exposure time is long
- P possibility of avoiding hazard or limiting harm
- P1 possible under specific conditions
- P2 scarcely possible

Figure A.1 Risk graph for determining required PL_r for safety function

Annex B (informative)

Block method and safety-related block diagram

B.1 Block method

The simplified approach requires a block-oriented logical representation of the SRP/CS. The SRP/CS should be separated into a small number of blocks according to the following:

- blocks should represent logical units of the SRP/CS related to the execution of the safety function;
- different channels performing the safety function should be separated into different blocks—if one block is no longer able to perform its function, the execution of the safety function through the blocks of the other channel should not be affected;
- each channel may consist of one or several blocks—three blocks per channel in the designated architectures, input, logic and output, is not an obligatory number, but simply an example for a logical separation inside each channel;
- each hardware unit of the SRP/CS should belong to exactly one block, thus allowing for the calculation of the $MTTF_d$ of the block based on the $MTTF_d$ of the hardware units belonging to the block (e.g. by failure mode and effects analysis or the parts count method, see Annex D.1);
- hardware units only used for diagnostics (e.g. test equipment) and which do not affect the execution of the safety function in the different channels when they fail dangerously, may be separated from hardware units necessary for the execution of the safety function in the different channels.

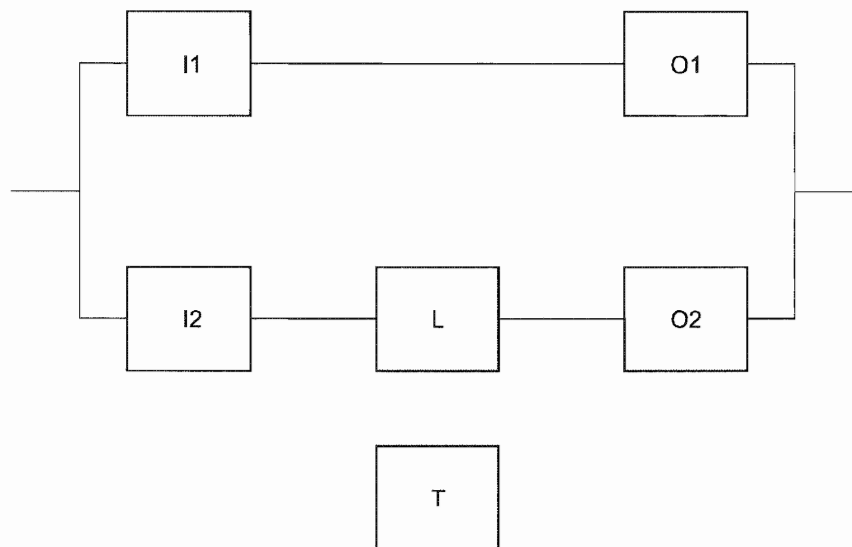
NOTE : For the purposes of this Standard, “blocks” do not correspond to functional blocks or reliability blocks.

B.2 Safety-related block diagram

The blocks defined by the block method may be used to graphically represent the logical structure of the SRP/CS in a safety-related block diagram. For such a graphical representation, the following may be of guidance:

- the failure of one block in a series alignment of blocks leads to the failure of the whole channel (e.g. if one hardware unit in one channel of the SRP/CS fails dangerously, the whole channel might not be able to execute the safety function any longer);
- only the dangerous failure of all channels in a parallel alignment leads to the loss of the safety function (e.g. a safety function performed by several channels is executed as long as at least one channel has no failure);
- blocks used only for testing purposes and which do not affect the execution of the safety function in the different channels when they fail dangerously may be separated from blocks in the different channels.

See figure B.1 for an example.



I1 and O1 build up the first channel (series alignment); while I2, L and O2 build up the second channel (series alignment), with both channels executing the safety function redundantly (parallel alignment). T is only used for testing.

Key

I1, I2 input devices, e.g. sensor
L logic
O1, O2 output devices, e.g. main contactor
T testing device

Figure B.1 Example of safety-related block diagram

Annex C (informative)

Calculating or evaluating MTTF_d values for single components

C.1 General

This Annex gives several methods for calculating or evaluating MTTF_d values for single components: the method given in **C.2** is based on the respect of good engineering practices for the different kinds of components; that given in **C.3** is applicable to hydraulic components; **C.4** provides a means of calculating the MTTF_d of pneumatic, mechanical and electromechanical components from B_{10} (see **C.4.1**); **C.5** lists MTTF_d values for electrical components.

C.2 Good engineering practices method

If the following criteria are met, the MTTF_d or B_{10d} value for a component can be estimated according to table C.1.

- a) The components are manufactured according to basic and well-tried safety principles in accordance with **ISO 13849-2**, or the relevant standard (see table C.1) for the design of the component (confirmation in the data sheet of the component).

NOTE : This information can be found in the data sheet of the component manufacturer.

- b) The manufacturer of the component specifies the appropriate application and operating conditions for the user.
- c) The design of the SRP/CS fulfils the basic and well-tried safety principles according to **ISO 13849-2**, for the implementation and operation of the component.

C.3 Hydraulic components

If the following criteria are met, the MTTF_d value for a single hydraulic component, e.g. valve, can be estimated at 150 years.

- a) The hydraulic components are manufactured according to basic and well-tried safety principles in accordance with **ISO 13849-2**, tables C.1 and C.2, for the design of the hydraulic component (confirmation in the data sheet of the component).

NOTE : This information can be found in the data sheet of the component manufacturer.

- b) The manufacturer of the hydraulic component specifies the appropriate application and operating conditions for the user. The SRP/CS manufacturer shall provide information pertaining to his responsibility to apply the basic and well-tried safety principles according to **ISO 13849-2**, tables C.1 and C.2, for the implementation and operation of the hydraulic component.

But if either **a)** or **b)** is not achieved, the MTTF_d value for the single hydraulic component has to be given by the manufacturer.

Table C.1 International Standards, JISs and other standards dealing with $MTTF_d$ or B_{10d} for components

	Basic and well-tried safety principles according to ISO 13849-2:2003	Other relevant standards	Typical values: $MTTF_d$ (years) B_{10d} (cycles)
Mechanical components	Tables A.1 and A.2	—	$MTTF_d = 150$
Hydraulic components	Tables C.1 and C.2	JIS B 8361 EN 982	$MTTF_d = 150$
Pneumatic components	Tables B.1 and B.2	JIS B 8370 EN 983	$B_{10d} = 20\,000\,000$
Relays and contactor relays with small load (mechanical load)	Tables D.1 and D.2	EN 50205 IEC 61810 series JIS C 8201 series	$B_{10d} = 20\,000\,000$
Relays and contactor relays with maximum load	Tables D.1 and D.2	EN 50205 IEC 61810 series JIS C 8201 series	$B_{10d} = 400\,000$
Proximity switches with small load (mechanical load)	Tables D.1 and D.2	JIS C 8201 series JIS B 9710	$B_{10d} = 20\,000\,000$
Proximity switches with maximum load	Tables D.1 and D.2	JIS C 8201 series JIS B 9710	$B_{10d} = 400\,000$
Contactors with small load (mechanical load)	Tables D.1 and D.2	JIS C 8201 series	$B_{10d} = 20\,000\,000$
Contactors with nominal load	Tables D.1 and D.2	JIS C 8201 series	$B_{10d} = 2\,000\,000$
Position switches independent of load ^{a)}	Tables D.1 and D.2	JIS C 8201 series JIS B 9710	$B_{10d} = 20\,000\,000$
Position switches (with separate actuator, guard-locking) independent of load ^{a)}	Tables D.1 and D.2	JIS C 8201 series JIS B 9710	$B_{10d} = 2\,000\,000$
Emergency stop devices independent of the load ^{a)}	Tables D.1 and D.2	JIS C 8201 series JIS B 9703	$B_{10d} = 100\,000$
Emergency stop devices with maximum operational demands ^{a)}	Tables D.1 and D.2	JIS C 8201 series JIS B 9703	$B_{10d} = 6\,050$
Push buttons (e.g. enabling switches independent of the load) ^{a)}	Tables D.1 and D.2	JIS C 8201 series	$B_{10d} = 100\,000$
For the definition and use of B_{10d} , see C.4 .			
NOTE 1 B_{10d} is estimated as two times B_{10} (50 % dangerous failure).			
NOTE 2 “Small load” means, for example, 20 % of the rated value (for more information, see ISO 13849-2).			
Note ^{a)} If fault exclusion for direct opening action is possible.			

C.4 MTTF_d of pneumatic, mechanical and electromechanical components

C.4.1 General

For pneumatic, mechanical and electromechanical components (pneumatic valves, relays, contactors, position switches, cams of position switches, etc.) it may be difficult to calculate the mean time to dangerous failure (MTTF_d for components), which is given in years and which is required by this Standard. Most of the time, the manufacturers of these kinds of components only give the mean number of cycles until 10 % of the components fail dangerously (B_{10d}). This clause gives a method for calculating an MTTF_d for components by using B_{10d} or T (lifetime) given by the manufacturer related closely to the application dependent cycles.

If the following criteria are met, the MTTF_d value for a single pneumatic, electro-mechanical or mechanical component can be estimated according to C.4.2.

- a) The components are manufactured according to basic safety principles in accordance with **ISO 13849-2**, table B.1 or table D.1, for the design of the component (confirmation in the data sheet of the component).

NOTE : This information can be found in the data sheet of the component manufacturer.

- b) The components to be used in category 1, 2, 3 or 4 are manufactured according to well-tried safety principles in accordance with **ISO 13849-2**, table B.2 or table D.2, for the design of the component (confirmation in the data sheet of the component).

NOTE : This information can be found in the data sheet of the component manufacturer.

- c) The manufacturer of the component specifies the appropriate application and operating conditions for the user. The SRP/CS manufacturer shall provide information pertaining to his responsibility to fulfil the basic safety principles according to **ISO 13849-2**, table B.1 or table D.1, for the implementation and operation of the component. For category 1, 2, 3 or 4, the user has to be informed of his responsibility to fulfil the well-tried safety principles according to **ISO 13849-2**, table B.2 or table D.2, for the implementation and operation of the component.

C.4.2 Calculation of MTTF_d for components from B_{10d}

The mean number of cycles until 10 % of the components fail dangerously (B_{10d})¹⁾ should be determined by the manufacturer of the component in accordance with relevant product standards for the test methods (e.g. **JIS C 8201-5-1**, **ISO 19973** series, **IEC 61810** series). The dangerous failure modes of the component have to be defined, e.g. sticking at an end position or change of switching times. If not all the components fail dangerously during the tests (e.g. seven components tested, only five fail dangerously), an analysis taking into account the components that were not dangerously failed components should be performed.

With B_{10d} ¹⁾ and n_{op} , the mean number of annual operations, MTTF_d for components can be calculated as

Note ¹⁾ If the dangerous fraction of B_{10} is not given, 50 % of B_{10} may be used, so $B_{10d} = 2B_{10}$ is recommended.

$$\text{MTTF}_d = \frac{B_{10d}}{0.1 \times n_{op}} \dots\dots\dots (\text{C.1})$$

where

$$n_{op} = \frac{d_{op} \times h_{op} \times 3\,600 \text{ s/h}}{t_{cycle}} \dots\dots\dots (\text{C.2})$$

with the following assumptions having been made on the application of the component:

- h_{op} : the mean operation, in hours per day;
- d_{op} : the mean operation, in days per year;
- t_{cycle} : the mean time between the beginning of two successive cycles of the component. (e.g. switching of a valve) in seconds per cycle.

The operation time of the component is limited to T_{10d} , the mean time until 10 % of the components fail dangerously.

$$T_{10d} = \frac{B_{10d}}{n_{op}} \dots\dots\dots (\text{C.3})$$

NOTE : Explanation of the formulas in **C.4.2**.

B_{10d} , the mean number of cycles till 10 % of the components fail dangerously, can be converted to T_{10d} , the mean time until 10 % of the components fail dangerously, by using n_{op} , the mean number of annual operations:

$$T_{10d} = \frac{B_{10d}}{n_{op}} \dots\dots\dots (\text{C.4})$$

The reliability methods in this Standard assume that the failure of components is distributed exponentially over time: $F(t) = 1 - \exp(-\lambda_d t)$. For pneumatic and electromechanical components, a weibull distribution is more likely. But if the operation time of the components is limited to the mean time until 10 % of the components fail dangerously (T_{10d}), then a constant dangerous failure rate (λ_d) over this operation time can be estimated as

$$\lambda_d = \frac{0.1}{T_{10d}} = \frac{0.1 \times n_{op}}{B_{10d}} \dots\dots\dots (\text{C.5})$$

Equation (C.5) takes into account that with a constant failure rate, 10 % of the components in the assumed application fail after T_{10d} [years], corresponding to B_{10d} [cycle]. To be exact:

$$F(T_{10d}) = 1 - \exp(-\lambda_d T_{10d}) = 10 \% \text{ means } \lambda_d = \frac{\ln(0.9)}{T_{10d}} = \frac{0.105\,36}{T_{10d}} = \frac{0.1}{T_{10d}} \dots\dots (\text{C.6})$$

With $\text{MTTF}_d = 1/\lambda_d$ for exponential distributions, this yields

$$\text{MTTF}_d = \frac{T_{10d}}{0.1} = \frac{B_{10d}}{0.1 \times n_{op}} \dots\dots\dots (\text{C.7})$$

C.4.3 Example

For a pneumatic valve, a manufacturer determines a mean value of 60 million cycles as B_{10d} . The valve is used for two shifts each day on 220 operation days a year. The mean time between the beginning of two successive switching of the valve is estimated as 5 s. This yields the following values:

- d_{op} of 220 days per year;
- h_{op} of 16 h per day;
- t_{cycle} of 5 s per cycle;
- B_{10d} of 60 million cycles.

With these input data the following quantities can be calculated:

$$n_{op} = \frac{220 \text{ days/year} \times 16 \text{ h/day} \times 3\,600 \text{ s/h}}{5 \text{ s/cycle}} = 2.53 \times 10^6 \text{ cycles/year} \dots (C.8)$$

$$T_{10d} = \frac{60 \times 10^6 \text{ cycles}}{2.53 \times 10^6 \text{ cycles/year}} = 23.7 \text{ years} \dots (C.9)$$

$$MTTF_d = \frac{23.7 \text{ years}}{0.1} = 237 \text{ years} \dots (C.10)$$

This will give an $MTTF_d$ for the component “high” according to table 5. These assumptions are only valid for a restricted operation time of 23.7 years for the valve.

C.5 $MTTF_d$ data of electrical components

C.5.1 General

Tables C.2 to C.7 indicate some typical average values of $MTTF_d$ for electronic components. The data are extracted from the **SN 29500** series database^[51]. All data are of general type. Various databases available (see the database list in the Bibliography) which present $MTTF_d$ values for various electronic components. If the designer of an SRP/CS has other, reliable, specific data on the components used, then the use of that specific data instead is highly recommended.

The values given in tables C.2 to C.7 are valid for a temperature of 40 °C, nominal load for current and voltage.

In the $MTTF$ column of the tables, the values from **SN 29500** are for generic components for all possible failure modes which are not necessarily dangerous failures. In the $MTTF_d$ column, it is typically assumed that not all failure modes lead to a dangerous failure. This depends mainly on the application. A precise way of determining the “typical” $MTTF_d$ for components is to carry out an FMEA. Some components, e.g. transistors used as switches, can have short circuits or interruptions as failure. Only one of these two modes can be dangerous; therefore the “remarks” column assumes only 50 % dangerous failure, which means that the $MTTF_d$ for components is twice the given $MTTF$ value. For use where there is doubt, a worst case $MTTF_d$ for components is given in the “worst case” $MTTF_d$ column, where the safety margin is 10.

C.5.2 Semiconductors

See tables C.2 and C.3.

Table C.2 Transistors (used as switches)

Transistor	Example	MTTF for components years	MTTF _d for components years		Remark
			Typical	Worst case	
Bipolar	TO18, TO92, SOT23	34 247	68 493	6 849	50 % dangerous failure
Bipolar, low power	TO5, TO39	5 708	11 416	1 142	50 % dangerous failure
Bipolar, power	TO3, TO220, D-Pack	1 941	3 881	388	50 % dangerous failure
FET	Junction MOS	22 831	45 662	4 566	50 % dangerous failure
MOS, power	TO3, TO220, D-Pack	1 142	2 283	228	50 % dangerous failure

Table C.3 Diodes, power semiconductors and integrated circuits

Diode	Example	MTTF for components years	MTTF _d for components years		Remark
			Typical	Worst case	
General purpose	—	114 155	228 311	22 831	50 % dangerous failure
Suppressor	—	15 981	31 963	3 196	50 % dangerous failure
Zener diode $P_{tot} < 1 \text{ W}$	—	114 155	228 311	22 831	50 % dangerous failure
Rectifier diodes	—	57 078	114 155	11 416	50 % dangerous failure
Rectifier bridges	—	11 415	22 831	2 283	50 % dangerous failure
Thyristors	—	2 283	4 566	457	50 % dangerous failure
Triacs, Diacs	—	1 484	2 968	297	50 % dangerous failure
Integrated circuits (programmable and non-programmable)	Use manufacturer's data				50 % dangerous failure

C.6 Passive components

See tables C.4 to C.7.

Table C.4 Capacitors

Capacitor	Example	MTTF for components years	MTTF _d for components years		Remark
			Typical	Worst case	
Standard, no power	KS, KP, KC, KT, MKT, MKC, MKP, MKU, MP, MKV	57 078	114 155	11 416	50 % dangerous failure
Ceramic	—	22 831	45 662	4 566	50 % dangerous failure
Aluminium electrolytic	Non-solid electrolyte	22 831	45 662	4 566	50 % dangerous failure
Aluminium electrolytic	Solid electrolyte	37 671	75 342	7 534	50 % dangerous failure
Tantalum electrolytic	Non-solid electrolyte	11 415	22 831	2 283	50 % dangerous failure
Tantalum electrolytic	Solid electrolyte	114 155	228 311	22 831	50 % dangerous failure

Table C.5 Resistors

Resistor	Example	MTTF for components years	MTTF _d for components years		Remark
			Typical	Worst case	
Carbon film	—	114 155	228 311	22 831	50 % dangerous failure
Metal film	—	570 776	1 141 552	114 155	50 % dangerous failure
Metal oxide and wire-wound	—	22 831	45 662	4 566	50 % dangerous failure
Variable	—	3 767	7 534	753	50 % dangerous failure

Table C.6 Inductors

Inductor	Example	MTTF for components years	MTTF _d for components years		Remark
			Typical	Worst case	
For MC application	—	37 671	75 342	7 534	50 % dangerous failure
Low frequency inductors and transformers	—	22 831	45 662	4 566	50 % dangerous failure
Main transformers and transformers for switched modes and power supplies	—	11 415	22 831	2 283	50 % dangerous failure

Table C.7 Optocouplers

Optocouplers	Example	MTTF for components years	MTTF _d for components years		Remark
			Typical	Worst case	
Bipolar output	SFH 610	7 648	15 296	1 530	50 % dangerous failure
FET output	LH 1056	2 854	5 708	571	50 % dangerous failure

Annex D (informative)

Simplified method for estimating MTTF_d for each channel

D.1 Parts count method

Use of the “parts count method” serves to estimate the MTTF_d for each channel separately. The MTTF_d values of all single components which are part of that channel are used in this calculation.

The general formula is

$$\frac{1}{\text{MTTF}_d} = \sum_{i=1}^{\tilde{N}} \frac{1}{\text{MTTF}_{d_i}} = \sum_{j=1}^{\tilde{N}} \frac{n_j}{\text{MTTF}_{d_j}} \dots\dots\dots (\text{D.1})$$

where

MTTF_d : for the complete channel;

MTTF_{d_i}, MTTF_{d_j} : the MTTF_d of each component which has a contribution to the safety function

The first sum is over each component separately; the second sum is an equivalent, simplified form where all n_j identical components with the same MTTF_{d_j} are grouped together.

Example :

$$1/\text{MTTF}_{d_i} = 1/30 + 1/30 + 1/30$$

$$n_j/\text{MTTF}_{d_j} = 3/30 = 1/10$$

The example given in table D.1 gives an MTTF_d of the channel of 21.4 years, which is “medium” according to table 5.

Table D.1 Example of the parts list of a circuit board

J	Component	Units n_j	MTTF _{d_j} Worst case years	1/MTTF _{d_j} Worst case 1/year	n_j/MTTF_{d_j} Worst case 1/year
1	Transistors, bipolar, low power (see table C.2)	2	1 142	0.000 876	0.001 752
2	Resistor, carbon film (see table C.5)	5	22 831	0.000 044	0.000 219
3	Capacitor, standard, no power (see table C.4)	4	11 416	0.000 088	0.000 350
4	Relay (with small load, see table C.1) ($B_{10d} = 20\,000\,000$ cycles, $n_{op} = 633\,600$)	4	315.66	0.003 168	0.012 672
5	Contactors (with nominal load, see table C.1) ($B_{10d} = 2\,000\,000$ cycles, $n_{op} = 633\,600$)	1	31.57	0.031 676	0.031 676
$\Sigma(n_j/\text{MTTF}_{d_j})$					0.046 669
MTTF _d = $1/\Sigma(n_j/\text{MTTF}_{d_j})$ [years]		21.43			

NOTE 1 This method is based on the presumption that a dangerous failure of any component within a channel leads to dangerous failure of the channel. The $MTTF_d$ calculation illustrated by table D.1 is based upon this.

NOTE 2 In this example, the main influence comes from the contactor. The chosen values for $MTTF_d$ and B_{10d} for this example are based on Annex C. For the example application $d_{op}=220$ days/year, $h_{op}=8$ h/day and $t_{cycle}=10$ s/cycle is assumed, giving $n_{op}=633\,600$ cycles/year. In general, taking manufacturer's values for $MTTF_d$ and B_{10d} will lead to a much better result, that is, a higher $MTTF_d$ for the channel.

D.2 $MTTF_d$ for different channels, symmetrization of $MTTF_d$ for each channel

The designated architectures of 6.2 assume that for different channels in a redundant SRP/CS the values for $MTTF_d$ for each channel are the same. This value per channel should be input for figure 5.

If the $MTTF_d$ of the channels differ, there are two possibilities:

- as a worst case assumption, the lower value should be taken into account;
- Formula D.2 can be used as an estimation of a value that can be substituted for $MTTF_d$ for each channel:

$$MTTF_d = \frac{2}{3} \left[MTTF_{dC1} + MTTF_{dC2} - \frac{1}{\frac{1}{MTTF_{dC1}} + \frac{1}{MTTF_{dC2}}} \right] \dots\dots\dots (D.2)$$

where $MTTF_{dC1}$ and $MTTF_{dC2}$ are the values for two different redundant channels.

Example :

One channel has an $MTTF_{dC1}=3$ years, the other channel has an $MTTF_{dC2}=100$ years, then the resulting $MTTF_d=66$ years for each channel. This means a redundant system with 100 years $MTTF_d$ in one channel and 3 years $MTTF_d$ in the other channel is equal to a system where each channel has an $MTTF_d$ of 66 years.

A redundant system with two channels and different $MTTF_d$ values for each channel can be substituted by a redundant system with identical $MTTF_d$ in each channel by using the above formula. This procedure is necessary for the correct use of figure 5.

NOTE : This method assumes independent parallel channels.

Annex E (informative)

Estimates for diagnostic coverage (DC) for functions and modules

E.1 Examples of diagnostic coverage (DC)

See table E.1

Table E.1 Estimates for diagnostic coverage (DC)

Measure		DC
EI	Input device	
1	Cyclic test stimulus by dynamic change of the input signals	90 %
2	Plausibility check, e.g. use of normally open and normally closed mechanically linked contacts	99 %
3	Cross monitoring of inputs without dynamic test	0 % to 99 %, depending on how often a signal change is done by the application
4	Cross monitoring of input signals with dynamic test if short circuits are not detectable (for multiple I/O)	90 %
5	Cross monitoring of input signals and intermediate results within the logic (L), and temporal and logical software monitor of the program flow and detection of static faults and short circuits (for multiple I/O)	99 %
6	Indirect monitoring (e.g. monitoring by pressure switch, electrical position monitoring of actuators)	90 % to 99 %, depending on the application
7	Direct monitoring (e.g. electrical position monitoring of control valves, monitoring of electromechanical devices by mechanically linked contact elements)	99 %
8	Fault detection by the process	0 % to 99 %, depending on the application; this measure alone is not sufficient for the required performance level "e"!
9	Monitoring some characteristics of the sensor (response time, range of analogue signals, e.g. electrical resistance, capacitance)	60 %
EL	Logic	
1	Indirect monitoring (e.g. monitoring by pressure switch, electrical position monitoring of actuators)	90 % to 99 %, depending on the application
2	Direct monitoring (e.g. electrical position monitoring of control valves, monitoring of electromechanical devices by mechanically linked contact elements)	99 %
3	Simple temporal time monitoring of the logic (e.g. timer as watchdog, where trigger points are within the program of the logic)	60 %
4	Temporal and logical monitoring of the logic by the watchdog, where the test equipment does plausibility checks of the behaviour of the logic	90 %

Table E.1 (continued)

	Measure	DC
5	Start-up self-tests to detect latent faults in parts of the logic (e.g. program and data memories, input/output ports, interfaces)	90 % (depending on the testing technique)
6	Checking the monitoring device reaction capability (e.g. watchdog) by the main channel at start-up or whenever the safety function is demanded or whenever an external signal demands it, through an input facility	90 %
7	Dynamic principle (all components of the logic are required to change the state ON-OFF-ON when the safety function is demanded), e.g. interlocking circuit implemented by relays	99 %
8	Invariable memory: signature of one word (8 bit)	90 %
9	Invariable memory: signature of double word (16 bit)	99 %
10	Variable memory: RAM-test by use of redundant data e.g. flags, markers, constants, timers and cross comparison of these data	60 %
11	Variable memory: check for readability and write ability of used data memory cells	60 %
12	Variable memory: RAM monitoring with modified Hamming code or RAM self-test (e.g. "galpat" or "Abraham")	99 %
13	Processing unit: self-test by software	60 % to 90 %
14	Processing unit: coded processing	90 % to 99 %
15	Fault detection by the process	0 % to 99 %, depending on the application; this measure alone is not sufficient for the required performance level "e"!
EO	Output device	
1	Monitoring of outputs by one channel without dynamic test	0 % to 99 % depending on how often a signal change is done by the application
2	Cross monitoring of outputs without dynamic test	0 % to 99 % depending on how often a signal change is done by the application
3	Cross monitoring of output signals with dynamic test without detection of short circuits (for multiple I/O)	90 %
4	Cross monitoring of output signals and intermediate results within the logic (L) and temporal and logical software monitor of the program flow and detection of static faults and short circuits (for multiple I/O)	99 %
5	Redundant shut-off path with no monitoring of the actuator	0 %
6	Redundant shut-off path with monitoring of one of the actuators either by logic or by test equipment	90 %
7	Redundant shut-off path with monitoring of the actuators by logic and test equipment	99 %
8	Indirect monitoring (e.g. monitoring by pressure switch, electrical position monitoring of actuators)	90 % to 99 %, depending on the application

Table E.1 (concluded)

Measure		DC
9	Fault detection by the process	0 % to 99 %, depending on the application; this measure alone is not sufficient for the required performance level “e”!
10	Direct monitoring (e.g. electrical position monitoring of control valves, monitoring of electromechanical devices by mechanically linked contact elements)	99 %
NOTE 1 For additional estimations for DC, see, e.g., IEC 61508-2 , tables A.2 to A.15.		
NOTE 2 If medium or high DC is claimed for the logic, at least one measure for variable memory, invariable memory and processing unit with each DC at least 60 % has to be applied. There may also be measures that used other than those listed in this table.		

E.2 Estimation of average DC (DC_{avg})

In many systems, several measures for fault detection might be used. These measures could check different parts of the SRP/CS and have different DC. For an estimation of the PL according to figure 5 only one, average, DC for the whole SRP/CS performing the safety function is applicable.

DC may be determined as the ratio between the failure rate of detected dangerous failures and the failure rate of total dangerous failures. According to this definition an average diagnostic coverage DC_{avg} is estimated by the following formula:

$$DC_{avg} = \frac{\frac{DC_1}{MTTF_{d1}} + \frac{DC_2}{MTTF_{d2}} + \dots + \frac{DC_N}{MTTF_{dN}}}{\frac{1}{MTTF_{d1}} + \frac{1}{MTTF_{d2}} + \dots + \frac{1}{MTTF_{dN}}} \dots\dots\dots (E.1)$$

Here all components of the SRP/CS without fault exclusion have to be considered and summed up. For each block, the $MTTF_d$ and the DC are taken into account. DC in this formula means the ratio of the failure rate of detected dangerous failures of the part (regardless of the measures used to detect the failures) to the failure rate of all dangerous failures of the part. Thus, DC refers to the tested part and not to the testing device. Components without failure detection (e.g. which are not tested) have $DC = 0$ and contribute only to the denominator of DC_{avg} .

Annex F (informative)

Estimates for common cause failure (CCF)

F.1 Requirements for CCF

A comprehensive procedure for measures against CCF for sensors/actuators and separately for control logic is given, for example, in **IEC 61508-6**, Annex D. Not all measures given therein are applicable to the machinery site. The most important measures are given here.

NOTE : In this Standard, it is assumed that for redundant systems a β -factor according to **IEC 61508-6**, Annex D should be less than or equal to 2 %.

F.2 Estimation of effect of CCF

This quantitative process should be passed for the whole system. Every part of the safety-related parts of the control system should be considered.

Table F.1 lists the measures and contains associated values, based on engineering judgement, which represent the contribution each measure makes in the reduction of common cause failures.

For each listed measure, only the full score or nothing can be claimed. If a measure is only partly fulfilled, the score according to this measure is zero.

Table F.1 Scoring process and quantification of measures against CCF

No.	Measure against CCF	Score
1	Separation/Segregation	
	Physical separation between signal paths: separation in wiring/piping, sufficient clearances and creepage distances on printed-circuit boards.	15
2	Diversity	
	Different technologies/design or physical principles are used, for example: first channel programmable electronic and second channel hardwired, kind of initiation, pressure and temperature, Measuring of distance and pressure, digital and analogue. Components of different manufactures.	20
3	Design/application/experience	
3.1	Protection against over-voltage, over-pressure, over-current, etc.	15
3.2	Components used are well-tried.	5
4	Assessment/analysis	
	Are the results of a failure mode and effect analysis taken into account to avoid common-cause-failures in design.	5

Table F.1 (concluded)

No.	Measure against CCF	Score
5	Competence/training	
	Have designers/maintainers been trained to understand the causes and consequences of common cause failures?	5
6	Environmental	
6.1	Prevention of contamination and electromagnetic compatibility (EMC) against CCF in accordance with appropriate standards. Fluidic systems: filtration of the pressure medium, prevention of dirt intake, drainage of compressed air, e.g. in compliance with the component manufacturers' requirements concerning purity of the pressure medium. Electric systems: Has the system been checked for electromagnetic immunity, e.g. as specified in relevant standards against CCF? For combined fluidic and electric systems, both aspects should be considered.	25
6.2	Other influences Have the requirements for immunity to all relevant environmental influences such as, temperature, shock, vibration, humidity (e.g. as specified in relevant standards) been considered?	10
	Total	(max. achievable 100)
Total score		Measures for avoiding CCF ^{a)}
65 or better		Meets the requirements
Less than 65		Process failed ⇒ choose additional measures
Note ^{a)} Where technological measures are not relevant, points attached to this column can be considered in the comprehensive calculation.		

Annex G (informative)

Systematic failure

G.1 General

ISO 13849-2 gives a comprehensive list of measures against systematic failure which should be applied, such as basic and well-tried safety principles.

G.2 Measures for the control of systematic failures

The following measures should be applied.

- Use of de-energization (see **ISO 13849-2**)

The safety-related parts of the control system (SRP/CS) should be designed so that with loss of its power supply a safe state of the machine can be achieved or maintained.
- Measures for controlling the effects of voltage breakdown, voltage variations, over-voltage, undervoltage

SRP/CS behaviour in response to voltage breakdown, voltage variations, over-voltage, and undervoltage conditions should be predetermined so that the SRP/CS can achieve or maintain a safe state of the machine (see also **JIS B 9960-1** and **IEC 61508-7, A.8**).
- Measures for controlling or avoiding the effects of the physical environment (for example, temperature, humidity, water, vibration, dust, corrosive substances, electromagnetic interference and its effects)

SRP/CS behaviour in response to the effects of the physical environment should be predetermined so that the SRP/CS can achieve or maintain a safe state of the machine (see also, for example, **JIS C 0920, JIS B 9960-1**).
- Program sequence monitoring shall be used with SRP/CS containing software in order to detect defective program sequences

A defective program sequence exists if the individual elements of a program (e.g. software modules, subprograms or commands) are processed in the wrong sequence or period of time or if the clock of the processor is faulty (see **IEC 61508-7, A.9**).
- Measures for controlling the effects of errors and other effects arising from any data communication process (see **IEC 61508-2, 7.4.8**)

In addition, one or more of the following measures should be applied, taking into account the complexity of the SRP/CS and its PL:

- failure detection by automatic tests;
- tests by redundant hardware;
- diverse hardware;
- operation in the positive mode;
- mechanically linked contacts;

- direct opening action;
- oriented mode of failure;
- over-dimensioning by a suitable factor, where the manufacturer can demonstrate that derating will improve reliability — where over-dimensioning is appropriate, an over-dimensioning factor of at least 1.5 should be used.

See also **ISO 13849-2, D.3**.

G.3 Measures for avoidance of systematic failures

The following measures should be applied.

- Use of suitable materials and adequate manufacturing

Selection of material, manufacturing methods and treatment in relation to, e.g. stress, durability, elasticity, friction, wear, corrosion, temperature, conductivity, dielectric rigidity.
- Correct dimensioning and shaping

Consideration of, e.g. stress, strain, fatigue, temperature, surface roughness, tolerances, manufacturing.
- Proper selection, combination, arrangements, assembly and installation of components, including cabling, wiring and any interconnections

Apply appropriate standards and manufacturer's application notes, e.g. catalogue sheets, installation instructions, specifications, and use of good engineering practice.
- Compatibility

Use components with compatible operating characteristics.
- Withstanding specified environmental conditions

Design the SRP/CS so that it is capable of working in all expected environments and in any foreseeable adverse conditions, e.g. temperature, humidity, vibration and electromagnetic interference (EMI) (see **ISO 13849-2, D.2**).
- Use of components designed to an appropriate standard and having well-defined failure modes

To reduce the risk of undetected faults by the use of components with specific characteristics (see **IEC 61508-7, B.3.3**).

In addition, one or more of the following measures should be applied, taking into account the complexity of the SRP/CS and its PL.

- Hardware design review (e.g. by inspection or walk-through)

To reveal by reviews and analysis discrepancies between the specification and implementation (see **IEC 61508-7, B.3.7** and **B.3.8**).
- Computer-aided design tools capable of simulation or analysis

Perform the design procedure systematically and include appropriate automatic construction elements that are already available and tested (see **IEC 61508-7, B.3.5**).

- Simulation

Perform a systematic and complete inspection of an SRP/CS design in terms of both the functional performance and the correct dimensioning of their components (see **IEC 61508-7, B.3.6**).

G.4 Measures for avoidance of systematic failures during SRP/CS integration

The following measures should be applied during integration of the SRP/CS:

- functional testing;
- project management;
- documentation.

In addition, black-box testing should be applied, taking into account the complexity of the SRP/CS and its PL.

Annex H (informative)

Example of combination of several safety-related parts of the control system

Figure H.1 is a schematic diagram of the safety-related parts providing one of the functions controlling a machine actuator. This is not a functional/working diagram and is included only to demonstrate the principle of combining categories and technologies in this one function.

The control is provided through electronic control logic and a hydraulic directional valve. The risk is reduced by an AOPD, which detects access to the hazardous situation and prevents start-up of the fluidic actuator when the light beam is interrupted.

The safety-related parts which provide the safety function are: AOPD, electronic control logic, hydraulic directional valve and the interconnecting means.

These combined safety-related parts provide a stop function as a safety function. As the AOPD is interrupted, the outputs transfer a signal to the electronic control logic, which provides a signal to the hydraulic directional valve to stop the hydraulic flow as the output of the SRP/CS. At the machine, this stops the hazardous movement of the actuator.

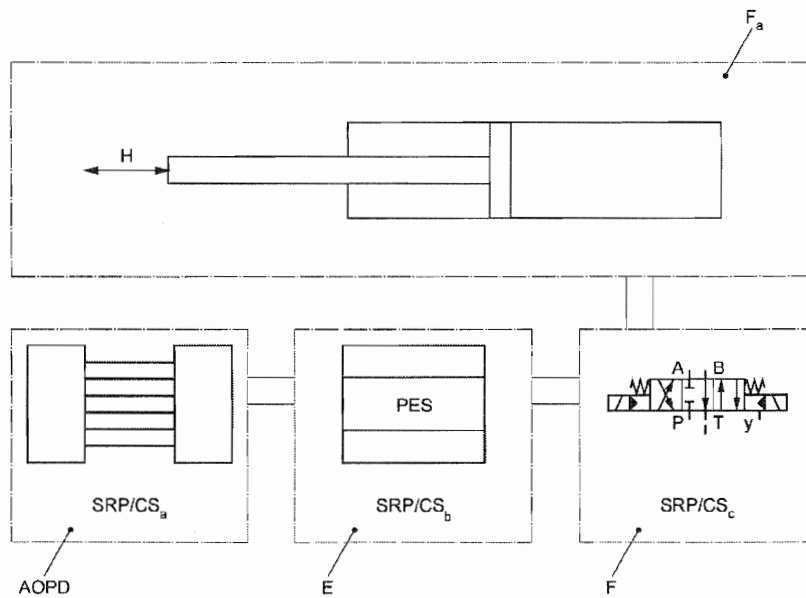
This combination of safety-related parts creates a safety function demonstrating the combination of different categories and technologies based on the requirements given in clause 6. Using the principles given in this Standard, the safety-related parts shown in figure H.2 can be described as follows.

- Category 2, $PL = c$ for the electro-sensitive protective device (light barrier). To reduce the probability of faults this device uses well-tried safety principles;
- Category 3, $PL = d$ for the electronic control logic. To increase the level of safety performance of this electronic control logic, the structure of this SRP/CS is redundant and implements several fault detection measures such that it is able to detect most of single faults;
- Category 1, $PL = c$ for the hydraulic directional valve. The status of being well-tried is mainly application-specific. In this example, the valve is considered to be well-tried. In order to reduce the probability of faults, this device is comprised of well-tried components applied using well-tried safety principles and all application conditions are considered (see 6.2.4).

NOTE 1 The position, size and layout of the interconnecting means have also to be taken into account.

This combination leads with $PL_{low} = c$ and $N_{low} = 2$ to an overall performance level of $PL = c$ (see 6.3).

NOTE 2 In case of one fault in the category 1 or the category 2 parts of figure H.2 there may be a loss of the safety function.



Key

AOPD active optoelectronic protective device (e.g. light barrier), SRP/CS_a: Category 2 [Type 2 (JIS B 9704-1)], PL=c

E electronic control logic, SRP/CS_b: Category 3, PL=d

F fluidics, SRP/CS_c: Category 1, PL=c

Fa fluidic actuator

H hazardous movement

Figure H.1 Example — Block diagram explaining combination of SRP/CS

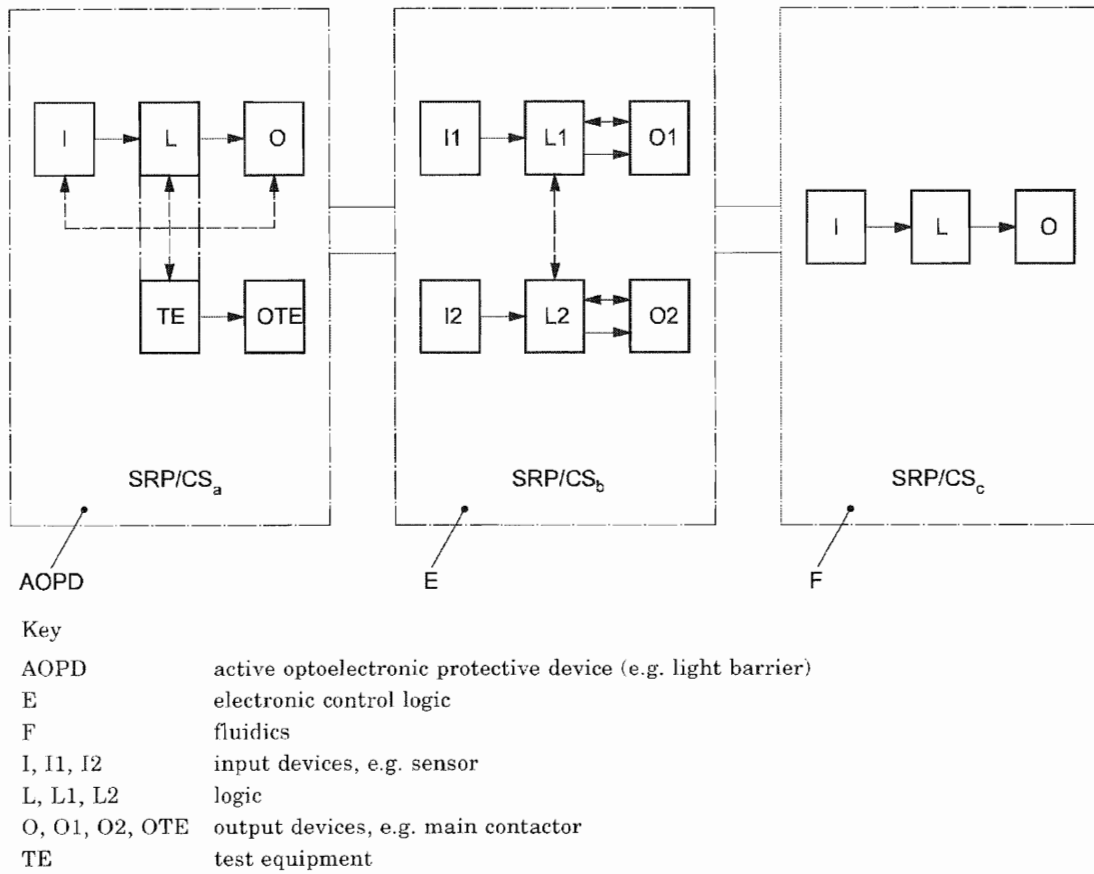


Figure H.2 Substitution of figure H.1 by designated architectures

Annex I (informative)

Examples

I.1 General

This Annex illustrates the use of the methods given in preceding annexes for identifying safety functions and determining PL. The quantification of two widely used control circuits is given. For the stepwise procedure, see figure 3.

Two different examples of control circuits, A and B are examined, see figure I.1 and figure I.3. Both illustrate the performance of the same safety function of the interlocking of the guard door. The first example is built up as one channel of electromechanical components with high $MTTF_d$ values, while the second is made up of two channels—one electromechanical and the other programmable electronic—including tests, but made up of components with lower $MTTF_d$.

I.2 Safety function and required performance level (PL_r)

For both examples, the safety function of the interlocking of a guard may be chosen as follows.

The dangerous movement will be stopped when the guard door is opened (by de-energizing the power of the electrical motor).

The risk parameters according to the risk graph method (see figure A.1) are the following:

- severity of injury, $S = S2$, serious;
- frequency and/or exposure time to hazard, $F = F1$, seldom to less often and/or the exposure time is short;
- possibility of avoiding the hazard, $P = P1$, possible under specific conditions.

These decisions lead to a required performance level PL_r of c.

Determination of the preferred category: a performance level of c can be achieved typically by very reliable single-channel systems (category 1) or redundant architectures (category 2 or 3) (see figure 5 and clause 6).

I.3 Example A, single-channel system

I.3.1 Identification of safety-related parts

All components contributing to the safety function are represented in figure I.1. Functional details not contributing to the safety function of interlocking (as start and stop switches) are omitted.

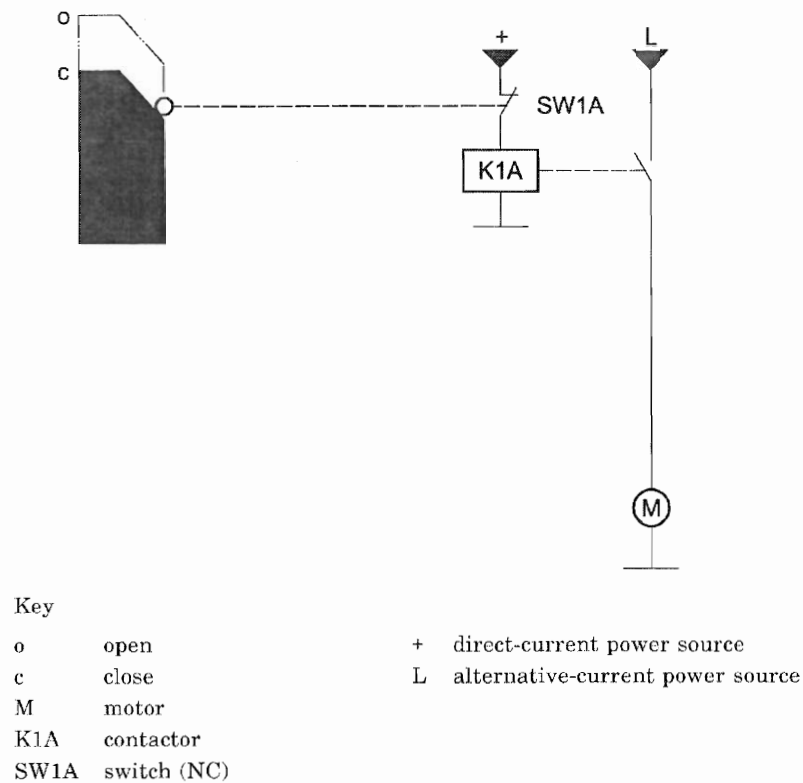


Figure I.1 Control circuit A for performing safety function

In this example, a door switch has normally closed contacts (but no fault exclusion is justified) and is connected to a contactor able to switch off the power connection to the motor:

- one channel of electromechanical components;
- switch SW1A has medium $MTTF_d$;
- contactor K1A has low $MTTF_d$.

The chosen contactor in this example is a well-tried component when implemented according to **ISO 13849-2**.

Thus the safety-related parts and their division into channels can be illustrated in a safety-related block diagram as shown in figure I.2.

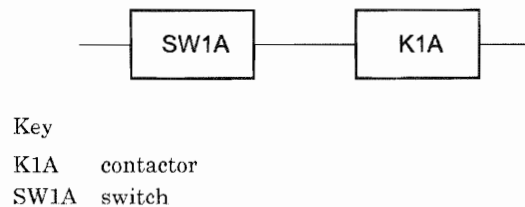


Figure I.2 Safety-related block diagram identifying safety-related parts of Example A

I.3.2 Quantification of $MTTF_d$ for each channel, DC_{avg} , common cause failure, category, PL

The values for $MTTF_d$ for each channel, DC_{avg} and common cause failure are assumed to be estimated according to Annexes C, D, E and F, or to be given by the manufacturer. The categories are estimated according to 6.2.

— $MTTF_d$

The contactor K1A and the switch SW1A contribute to the $MTTF_d$ of the one channel. The $MTTF_{d,K1A}$ of 50 years and $MTTF_{d,SW1A}$ of 20 years are assumed to be given by the manufacturer. The parts count method of D.1 yields for the $MTTF_d$ of the one channel:

$$\frac{1}{MTTF_d} = \frac{1}{MTTF_{SW1A}} + \frac{1}{MTTF_{K1A}} = \frac{1}{20 \text{ years}} + \frac{1}{50 \text{ years}} = \frac{0.07}{\text{years}} \dots (I.1)$$

which leads to $MTTF_d = 14.3$ years or “medium” for the channel according to 4.5.2, table 5.

NOTE : If no information for K1A were available, a worst case assumption according to C.2 or C.4 could be made.

— DC

Because no testing is done in control circuit A, the $DC = 0$ or “none” according to 4.5.3, table 6.

— Category

Although the preferred category for this circuit is category 1, the resulting $MTTF_d$ of the channel is “medium”. This is an argument that only category B is reached by this design.

Input data for figure 5: $MTTF_d$ for each channel is “medium” (14.3 years), DC_{avg} is “none” and category is B.

This may be interpreted as performance level b.

This result does not match the required performance level c according to I.2. The circuit thus has to be redesigned and re-evaluated until performance level c is reached, in order to meet the requirements for risk reduction of the example application of I.2.

I.4 Example B, redundant system

I.4.1 Identification of safety-related parts

All components contributing to the safety function are represented in figure I.3. Functional details not contributing to the safety function of interlocking (as start and stop switches or delayed switching of K1B) are omitted.

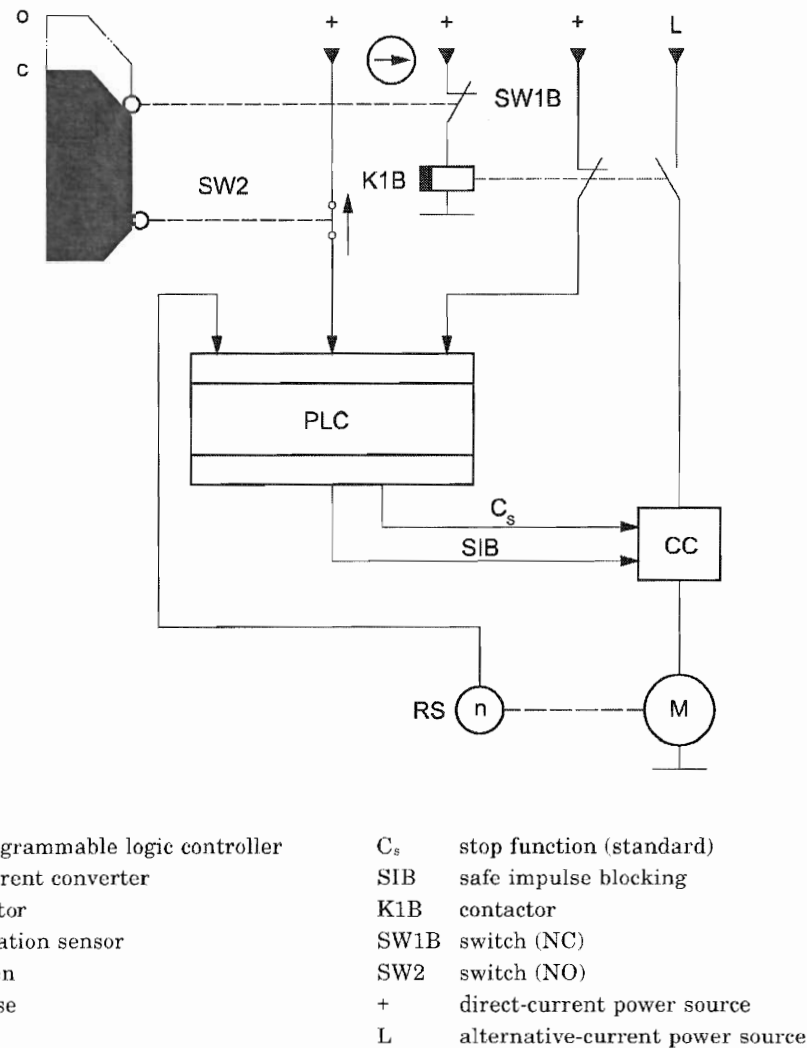


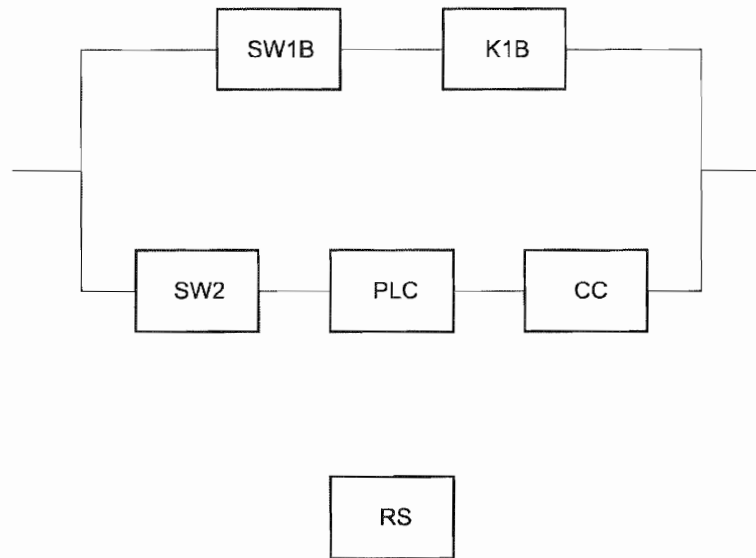
Figure I.3 Control circuit B to perform the safety function

In this second example two channels providing redundancy are used. The first channel, similarly to that in example A, uses a door switch having direct opening action and which is used in the positive mode of actuation. This door switch is connected to a contactor able to switch off the power connection to the motor. In the second channel additional (programmable) electronic components are used. A second door switch is connected to a programmable logic controller which can control the current converter to switch off the power connection to the motor:

- redundant channels, one electromechanical and the other programmable electronic;
- switch SW1B has positive mechanical action of the contacts, SW2 has medium $MTTF_d$;
- contactor K1B has medium $MTTF_d$, the chosen contactor in this example is not a well-tried component;
- electronic components have medium $MTTF_d$.

So the safety-related parts and their division into channels can be illustrated in a safety-related block diagram as shown in figure I.4.

NOTE : With respect to redundant diversity, requirements for software according to 4.6 for the PLC path are not considered relevant.



SW1B and K1B build up the first channel, SW2, PLC and CC build up the second channel; RS is only used to test the current converter.

Key

SW1B interlocking device

K1B contactor

SW2 switch

PLC programmable logic controller

CC current converter

RS rotation sensor

Figure I.4 Block diagrams identifying safety-related parts of example B

I.4.2 Quantification of $MTTF_d$ for each channel, DC_{avg} , common cause failure, category and PL

The values for $MTTF_d$ for each channel, DC_{avg} and common cause failure are assumed to be evaluated according to Annexes C, D, E and F, or to be given by the manufacturer. The categories are estimated according to 6.2.

The switch SW1B has a direct opening action and is used in the positive mode of actuation. Therefore, a fault exclusion is made concerning non-opening of a contact and non-actuation of the switch due to mechanical failure (e.g. break of plunger, wear of the actuating cam, maladjustment).

NOTE : These assumptions are valid for auxiliary circuit switches according to **JIS C 8201-5-1**, Annex K, and for adequate mechanical fixing and actuation of the switches according to the manufacturer's specification (see **ISO 13849-2**).

— $MTTF_d$

The contactor K1B is the only element contributing to the $MTTF_d$ of the one channel. The $MTTF_{K1B}$ of 30 years is assumed to be given by the manufacturer. The parts count method of **D.1** yields for the $MTTF_d$ of the one channel

$$\frac{1}{MTTF_{dC1}} + \frac{1}{MTTF_{dK1B}} \dots\dots\dots (I.2)$$

which leads to $MTTF_d = 30$ years for the channel.

In the second channel SW2, PLC and CC are contributing to $MTTF_{dC2}$. For these three components as well as for RS an $MTTF_d$ of 20 years is assumed to be given by the manufacturer. The parts count method of **D.1** yields for the $MTTF_{dC2}$ of the second channel

$$\begin{aligned} \frac{1}{MTTF_{dC2}} &= \frac{1}{MTTF_{dSW2}} + \frac{1}{MTTF_{dPLC}} + \frac{1}{MTTF_{dCC}} \\ &= \frac{1}{20 \text{ years}} + \frac{1}{20 \text{ years}} + \frac{1}{20 \text{ years}} = \frac{0.15}{\text{years}} \dots\dots\dots (I.3) \end{aligned}$$

which leads to $MTTF_d = 6.7$ years for the channel.

Because both channels have different $MTTF_d$, the formula of **D.2** can be used to calculate a substitutional value for a single-channel $MTTF_d$ of a symmetrical two-channel system. This formula yields $MTTF_d = 20$ years or “medium” for the channel according to **4.5.2**, table 5.

— DC

In control circuit B, four of the safety-related parts are tested by the PLC: SW2 and K1B are read back by the PLC, the PLC performs self-tests and the CC is read back via RS by the PLC. The related DC of every tested part are

- 1) $DC_{SW2} = 60 \%$, “low”, due to monitoring of input signals without dynamic test, see table E.1 (Input device, EI-3),
- 2) $DC_{K1B} = 99 \%$, “high”, due to normally open and normally closed mechanically linked contacts, see table E.1 (Input device, EI-2),
- 3) $DC_{PLC} = 30 \%$, “none”, due to low effectiveness of self-tests (it is assumed that the manufacturer has calculated this value by FMEA), and
- 4) $DC_{CC} = 90 \%$, “medium”, due to redundant shut-off path with monitoring of the actuator by control logic, see table E.1 (Output device, EO-6)—if the PLC monitors a failure of CC, it is able to stop the motion with the safe impulse blocking (additional shut-off path).

For an estimation of the PL, an average DC value (DC_{avg}) is needed as input for figure 5.

$$\begin{aligned}
 DC_{avg} &= \frac{\frac{DC_{SW2}}{MTTF_{dSW2}} + \frac{DC_{K1B}}{MTTF_{dK1B}} + \frac{DC_{PLC}}{MTTF_{dPLC}} + \frac{DC_{CC}}{MTTF_{dCC}}}{\frac{1}{MTTF_{dSW2}} + \frac{1}{MTTF_{dK1B}} + \frac{1}{MTTF_{dPLC}} + \frac{1}{MTTF_{dCC}}} \\
 &= \frac{\frac{0.6}{20 \text{ years}} + \frac{0.99}{30 \text{ years}} + \frac{0.3}{20 \text{ years}} + \frac{0.9}{20 \text{ years}}}{\frac{1}{20 \text{ years}} + \frac{1}{30 \text{ years}} + \frac{1}{20 \text{ years}} + \frac{1}{20 \text{ years}}} = \frac{0.123}{0.183} = 67.1 \% \dots (I.4)
 \end{aligned}$$

Thus, the DC_{avg} is “low” according to 4.5.3 and table 6.

— CCF

An estimation of the measures against CCF according to F.2 is assumed to have been carried out for control circuit B. Scores are claimed as given in table I.1.

Table I.1 Estimation of the measures against CCF for example B

No.	Item	Score for control circuit	Maximum possible score
1	Separation/segregation		
	Physical separation between signal paths	15	15
2	Diversity		
	Different technologies/design or physical principles are used	20	20
3	Design/application/experience		
3.1	Protection against overvoltage, overpressure, overcurrent, etc.	None	15
3.2	Components used are well-tried	5	5
4	Assessment/analysis		
	Are the results of a failure mode and effect analysis taken into account to avoid common cause failures in design?	5	5
5	Competence/training		
	Have designers been trained to understand the causes and consequences of common cause failures?	None	5
6	Environmental		
6.1	Prevention of contamination and electromagnetic compatibility (EMC) against CCF in accordance with appropriate standards	25	25
6.2	Other influences Have the requirements for immunity to all relevant environmental influences, such as temperature, shock, vibration, humidity (e.g. as specified in relevant standards) been considered?	10	10
	Total	80	Max. 100

Sufficient measures against CCF require a minimum score of 65. In example B, a score of 80 is sufficient to fulfil the requirements against CCF.

A single fault in any of the parts does not lead to the loss of the safety function. Whenever reasonably practicable the single fault is detected at or before the next demand upon the safety function. The diagnostic coverage (DC_{avg}) is in the range 60 % to 90 %. The measures against CCF are sufficient. These characteristics are typical for category 3.

Input data for figure 5: $MTTF_d$ for the channel is “medium” (20 years), DC_{avg} is “low” and category is 3.

This may be interpreted as performance level c.

This result matches the required performance level c of **1.2**. Thus control circuit B meets the requirements for risk reduction of the example application of **1.2**.

Annex J (informative)

Software

J.1 Description of example

In this Annex, exemplary activities for realizing the SRESW of an SRP/CS for $PL_r = d$ are presented. The SRP/CS is interfaced with the machine equipment. It ensures

- the acquisition of information sent by the various sensors,
- the processing required to operate the control elements taking into account the safety requirements, and
- the control of the actuators.

The design of the SRESW of this application on function block level is as shown in figure J.1.

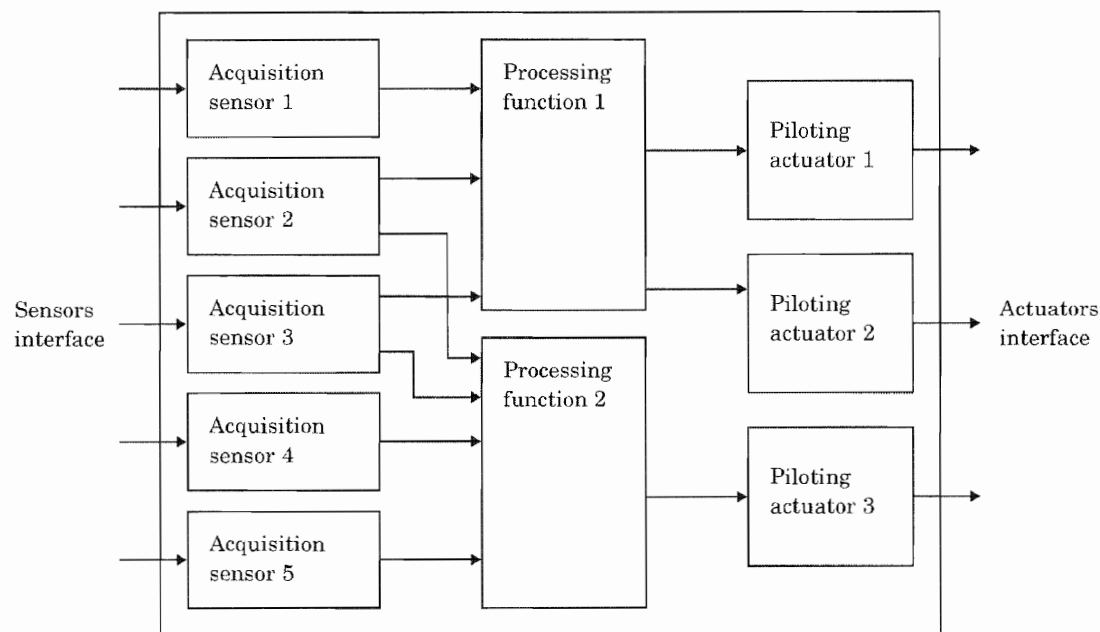


Figure J.1 Function block level design of software example

J.2 Application of V-model of software safety lifecycle

Table J.1 presents an exemplary synthesis of activities and documents on application of V-model of software safety lifecycle for a machine control.

Table J.1 Activities and documents within software safety lifecycle

Development activity	Verification activity	Associated documentation
Machine aspect: Identification of the functions involving the SRP/CS	Identification of safety-related functions	"Safety-related specification for machine control"
Architecture aspect: Definition of the control architecture with sensors and actuators	Comments upon safety characteristics of chosen components	"Definition of the control architecture"
Software specification aspect: Transcription of machine functions into software functions	Re-reading of the descriptions (see J.3)	"Software descriptions"
Software architecture aspect: To detail the functions into functional blocks	Definition of critical blocks which are subject to greater review and validation effort	"Function block modelling"
Encoding aspect: Encoding according to the programming rules (see J.4)	Re-reading of the code. Verification of functions and compliance with rules.	"Encoding comments in the code" "Encoding re-reading sheets"
Validation aspect: Making of test scenarios: operation aspect of functions behaviour-on-failure aspect	Verification of the test covering Verification of the test results	"Correspondence matrix" which cross-references specification paragraphs and tests "Test sheets" comprising test scenario and comments upon results achieved

J.3 Verification of software specification

As part of the software safety lifecycle, the verification activity at level of the software specification consists in reading the descriptions so as to verify that all the sensitive points are properly described. The following should be considered when verifying each function:

- limiting the cases of erroneous interpretation of the system specification;
- avoiding gaps in specification resulting in an a priori unknown behaviour of the SRP/CS;
- precisely defining conditions for activation and de-activation of functions;
- precisely guaranteeing that all the possible cases are handled;
- consistency tests;
- the different parameterizing cases;
- the reaction following a failure.

J.4 Example of programming rules

For the CCF, in general it should be possible to authenticate the program by author, date of loading, version and last type of access. Concerning the programming rules the following rules can be differentiated.

- a) **Programming rules at level of the program structure** The programming should be structured so as to display a consistent and understandable general skeleton allowing the different processings to be easily localized. This implies
- 1) use of templates for typical program or function blocks,
 - 2) partitioning of the program into segments in order to identify main parts corresponding to “inputs”, “processings” and “outputs”,
 - 3) comments on each program section in the source of the program to facilitate the updating of the comment in case of modification,
 - 4) description of the role a function block has when calling this block,
 - 5) that memory location should be used only by one single kind of data type and be marked by unique labels, and
 - 6) that the working sequence should not depend on variables such as a jump address calculated at runtime of the program, conditional jumps being authorized.
- b) **Programming rules regarding the use of variables**
- The activation or de-activation of any output should take place only once (centralized conditions).
 - The program should be structured such that the equations for updating a variable are centralized.
 - Each global variable, input or output, should have a mnemonic name explicit enough and be described by a comment within the source.
- c) **Programming rules at level of a function block**
- Preferably use function blocks that have been validated by the supplier of the SRP/CS, checking that the assumed operating conditions for these validated blocks correspond to the conditions of the program.
 - The size of the coded block should be limited to the following guideline values:
 - 1) parameters—maximum eight digital and two integer inputs, one output;
 - 2) function code—maximum ten local variables, maximum 20 Boolean equations.
 - The function blocks should not modify the global variables.
 - A digital value should be controlled relative to pre-set benchmarks to ensure the domain of validity.
 - A function block should try to detect inconsistencies of variables to be processed.
 - The fault code of a block should be accessible to discriminate a fault among others.
 - The fault codes and the state of the block after fault detection should be described by comments.
 - The resetting of the block or the restoration of a normal state should be described by comments.

Annex K (informative)

Numerical representation of figure 5

For $MTTF_d$, DC, categories and PL in figure 5, see table K.1.

Table K.1 Numerical representation of figure 5

MTTF _d for each channel years	Average probability of a dangerous failure per hour (1/h) and corresponding performance level (PL)													
	Cat. B DC _{avg} = none	PL	Cat. 1 DC _{avg} = none	PL	Cat. 2 DC _{avg} = low	PL	Cat. 2 DC _{avg} = medium	PL	Cat. 3 DC _{avg} = low	PL	Cat. 3 DC _{avg} = medium	PL	Cat. 4 DC _{avg} = high	PL
3	3.80 × 10 ⁻⁵	a			2.58 × 10 ⁻⁵	a	1.99 × 10 ⁻⁵	a	1.26 × 10 ⁻⁵	a	6.09 × 10 ⁻⁶	b		
3.3	3.46 × 10 ⁻⁵	a			2.33 × 10 ⁻⁵	a	1.79 × 10 ⁻⁵	a	1.13 × 10 ⁻⁵	a	5.41 × 10 ⁻⁶	b		
3.6	3.17 × 10 ⁻⁵	a			2.13 × 10 ⁻⁵	a	1.62 × 10 ⁻⁵	a	1.03 × 10 ⁻⁵	a	4.86 × 10 ⁻⁶	b		
3.9	2.93 × 10 ⁻⁵	a			1.95 × 10 ⁻⁵	a	1.48 × 10 ⁻⁵	a	9.37 × 10 ⁻⁶	b	4.40 × 10 ⁻⁶	b		
4.3	2.65 × 10 ⁻⁵	a			1.76 × 10 ⁻⁵	a	1.33 × 10 ⁻⁵	a	8.39 × 10 ⁻⁶	b	3.89 × 10 ⁻⁶	b		
4.7	2.43 × 10 ⁻⁵	a			1.60 × 10 ⁻⁵	a	1.20 × 10 ⁻⁵	a	7.58 × 10 ⁻⁶	b	3.48 × 10 ⁻⁶	b		
5.1	2.24 × 10 ⁻⁵	a			1.47 × 10 ⁻⁵	a	1.10 × 10 ⁻⁵	a	6.91 × 10 ⁻⁶	b	3.15 × 10 ⁻⁶	b		
5.6	2.04 × 10 ⁻⁵	a			1.33 × 10 ⁻⁵	a	9.87 × 10 ⁻⁶	b	6.21 × 10 ⁻⁶	b	2.80 × 10 ⁻⁶	c		
6.2	1.84 × 10 ⁻⁵	a			1.19 × 10 ⁻⁵	a	8.80 × 10 ⁻⁶	b	5.53 × 10 ⁻⁶	b	2.47 × 10 ⁻⁶	c		
6.8	1.68 × 10 ⁻⁵	a			1.08 × 10 ⁻⁵	a	7.93 × 10 ⁻⁶	b	4.98 × 10 ⁻⁶	b	2.20 × 10 ⁻⁶	c		
7.5	1.52 × 10 ⁻⁵	a			9.75 × 10 ⁻⁶	b	7.10 × 10 ⁻⁶	b	4.45 × 10 ⁻⁶	b	1.95 × 10 ⁻⁶	c		
8.2	1.39 × 10 ⁻⁵	a			8.87 × 10 ⁻⁶	b	6.43 × 10 ⁻⁶	b	4.02 × 10 ⁻⁶	b	1.74 × 10 ⁻⁶	c		
9.1	1.25 × 10 ⁻⁵	a			7.94 × 10 ⁻⁶	b	5.71 × 10 ⁻⁶	b	3.57 × 10 ⁻⁶	b	1.53 × 10 ⁻⁶	c		
10	1.14 × 10 ⁻⁵	a			7.18 × 10 ⁻⁶	b	5.14 × 10 ⁻⁶	b	3.21 × 10 ⁻⁶	b	1.36 × 10 ⁻⁶	c		
11	1.04 × 10 ⁻⁵	a			6.44 × 10 ⁻⁶	b	4.53 × 10 ⁻⁶	b	2.81 × 10 ⁻⁶	c	1.18 × 10 ⁻⁶	c		
12	9.51 × 10 ⁻⁶	b			5.84 × 10 ⁻⁶	b	4.04 × 10 ⁻⁶	b	2.49 × 10 ⁻⁶	c	1.04 × 10 ⁻⁶	c		
13	8.78 × 10 ⁻⁶	b			5.33 × 10 ⁻⁶	b	3.64 × 10 ⁻⁶	b	2.23 × 10 ⁻⁶	c	9.21 × 10 ⁻⁷	d		
15	7.61 × 10 ⁻⁶	b			4.53 × 10 ⁻⁶	b	3.01 × 10 ⁻⁶	b	1.82 × 10 ⁻⁶	c	7.44 × 10 ⁻⁷	d		
16	7.13 × 10 ⁻⁶	b			4.21 × 10 ⁻⁶	b	2.77 × 10 ⁻⁶	c	1.67 × 10 ⁻⁶	c	6.76 × 10 ⁻⁷	d		
18	6.34 × 10 ⁻⁶	b			3.68 × 10 ⁻⁶	b	2.37 × 10 ⁻⁶	c	1.41 × 10 ⁻⁶	c	5.67 × 10 ⁻⁷	d		
20	5.71 × 10 ⁻⁶	b			3.26 × 10 ⁻⁶	b	2.06 × 10 ⁻⁶	c	1.22 × 10 ⁻⁶	c	4.85 × 10 ⁻⁷	d		
22	5.19 × 10 ⁻⁶	b			2.93 × 10 ⁻⁶	c	1.82 × 10 ⁻⁶	c	1.07 × 10 ⁻⁶	c	4.21 × 10 ⁻⁷	d		
24	4.76 × 10 ⁻⁶	b			2.65 × 10 ⁻⁶	c	1.62 × 10 ⁻⁶	c	9.47 × 10 ⁻⁷	d	3.70 × 10 ⁻⁷	d		
27	4.23 × 10 ⁻⁶	b			2.32 × 10 ⁻⁶	c	1.39 × 10 ⁻⁶	c	8.04 × 10 ⁻⁷	d	3.10 × 10 ⁻⁷	d		

Tables K.1 (concluded)

	Average probability of a dangerous failure per hour (1/h) and corresponding performance level (PL)							
MTTF _d for each channel years	Cat. B PL DC _{avg} = none	Cat. 1 PL DC _{avg} = none	Cat. 2 PL DC _{avg} = low	Cat. 2 PL DC _{avg} = medium	Cat. 3 PL DC _{avg} = low	Cat. 3 PL DC _{avg} = medium	Cat. 4 PL DC _{avg} = high	
30		3.80 × 10 ⁻⁶ b	2.06 × 10 ⁻⁶ c	1.21 × 10 ⁻⁶ c	6.94 × 10 ⁻⁷ d	2.65 × 10 ⁻⁷ d	9.54 × 10 ⁻⁸ e	
33		3.46 × 10 ⁻⁶ b	1.85 × 10 ⁻⁶ c	1.06 × 10 ⁻⁶ c	5.94 × 10 ⁻⁷ d	2.30 × 10 ⁻⁷ d	8.57 × 10 ⁻⁸ e	
36		3.17 × 10 ⁻⁶ b	1.67 × 10 ⁻⁶ c	9.39 × 10 ⁻⁷ d	5.16 × 10 ⁻⁷ d	2.01 × 10 ⁻⁷ d	7.77 × 10 ⁻⁸ e	
39		2.93 × 10 ⁻⁶ c	1.53 × 10 ⁻⁶ c	8.40 × 10 ⁻⁷ d	4.53 × 10 ⁻⁷ d	1.78 × 10 ⁻⁷ d	7.11 × 10 ⁻⁸ e	
43		2.65 × 10 ⁻⁶ c	1.37 × 10 ⁻⁶ c	7.34 × 10 ⁻⁷ d	3.87 × 10 ⁻⁷ d	1.54 × 10 ⁻⁷ d	6.37 × 10 ⁻⁸ e	
47		2.43 × 10 ⁻⁶ c	1.24 × 10 ⁻⁶ c	6.49 × 10 ⁻⁷ d	3.35 × 10 ⁻⁷ d	1.34 × 10 ⁻⁷ d	5.76 × 10 ⁻⁸ e	
51		2.24 × 10 ⁻⁶ c	1.13 × 10 ⁻⁶ c	5.80 × 10 ⁻⁷ d	2.93 × 10 ⁻⁷ d	1.19 × 10 ⁻⁷ d	5.26 × 10 ⁻⁸ e	
56		2.04 × 10 ⁻⁶ c	1.02 × 10 ⁻⁶ c	5.10 × 10 ⁻⁷ d	2.52 × 10 ⁻⁷ d	1.03 × 10 ⁻⁷ d	4.73 × 10 ⁻⁸ e	
62		1.84 × 10 ⁻⁶ c	9.06 × 10 ⁻⁷ d	4.43 × 10 ⁻⁷ d	2.13 × 10 ⁻⁷ d	8.84 × 10 ⁻⁸ e	4.22 × 10 ⁻⁸ e	
68		1.68 × 10 ⁻⁶ c	8.17 × 10 ⁻⁷ d	3.90 × 10 ⁻⁷ d	1.84 × 10 ⁻⁷ d	7.68 × 10 ⁻⁸ e	3.80 × 10 ⁻⁸ e	
75		1.52 × 10 ⁻⁶ c	7.31 × 10 ⁻⁷ d	3.40 × 10 ⁻⁷ d	1.57 × 10 ⁻⁷ d	6.62 × 10 ⁻⁸ e	3.41 × 10 ⁻⁸ e	
82		1.39 × 10 ⁻⁶ c	6.61 × 10 ⁻⁷ d	3.01 × 10 ⁻⁷ d	1.35 × 10 ⁻⁷ d	5.79 × 10 ⁻⁸ e	3.08 × 10 ⁻⁸ e	
91		1.25 × 10 ⁻⁶ c	5.88 × 10 ⁻⁷ d	2.61 × 10 ⁻⁷ d	1.14 × 10 ⁻⁷ d	4.94 × 10 ⁻⁸ e	2.74 × 10 ⁻⁸ e	
100		1.14 × 10 ⁻⁶ c	5.28 × 10 ⁻⁷ d	2.29 × 10 ⁻⁷ d	1.01 × 10 ⁻⁷ d	4.29 × 10 ⁻⁸ e	2.47 × 10 ⁻⁸ e	

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